520 Rec'd PCT/PTO 02 DEC 1999

FORM PTO-1390 (REV 11-98)

U S DEPARTMENT OF COMMERCE PATENT AND TRADEMARK OFFICE

TRANSMITTAL LETTER TO THE UNITED STATES DESIGNATED/ELECTED OFFICE (DO/EO/US) CONCERNING A FILING UNDER 35 U.S.C. 371

ATTORNEY'S DOCKET NUMBER
Filed: December 2, 1999
520.37902X00

U S APPLICATION NO (If known see 37 CFR 1 5)
09/445088

INTERNATIONAL APPLICATION NO.	INTERNATIONAL FILING DATE	PRIORITY DATE CLAIMED
PCT/JP98/02435	02 June 1998 (2.06.98)	03 June 1997 (3.06.97)

TITLE OF INVENTION
IMAGE ENCODEING AND DECODING METHOD AND DEVICE

APPLICANT(S) FOR DO/EO/US
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IPE JC13 DEC 07 1999 PATENT & TRADEMARK OFFICE

Applicant herewith submits to the United States Designated/Elected Office (DO/EO/US) the following items and other information:

1. [X] This is a **FIRST** submission of items concerning a filing under 35 U.S.C. 371.
2. [ ] This is a **SECOND or SUBSEQUENT** submission of items concerning a filing under 35 U.S.C. 371.
3. [ ] This express request to begin national examination procedures (35 U.S.C. 371(f)) at any time rather than delay examination until the expiration of the applicable time limit set in 35 U.S.C. 371(b) and PCT Articles 22 and 39(l).
4. [X] A proper Demand for International Preliminary Examination was made by the 19th month from the earliest claimed priority date.
5. [X] A copy of the International Application as filed (35 U.S.C. 371(c)(2))
   a. [X] is transmitted herewith (required only if not transmitted by the International Bureau).
   b. [ ] has been transmitted by the International Bureau.
   c [ ] is not required, as the application was filed in the United States Receiving Office (RO/US).
6. [X] A translation of the International Application into English (35 U.S.C. 371(c)(2)).
7. [ ] Amendments to the claims of the International Application under PCT Article 19 (35 U.S.C. 371(c)(3))
   a. [ ] are transmitted herewith (required only if not transmitted by the International Bureau).
   b. [ ] have been transmitted by the International Bureau.
   c [ ] have not been made; however, the time limit for making such amendments has NOT expired.
   d. [ ] have not been made and will not be made.
8. [ ] A translation of the amendments to the claims under PCT Article 19 (35 U.S.C. 371(c)(3)).
9. [X] An oath or declaration of the inventor(s) (35 U.S.C. 371(c)(4)).
10. [ ] A translation of the annexes to the International Preliminary Examination Report under PCT Article 36 (35 U.S.C. 371(c)(5)).

Items 11. to 16. below concern document(s) or information included:

11. [ ] An Information Disclosure Statement under 37 CFR 1.97 and 1.98.
12. [X] An assignment document for recording. A separate cover sheet in compliance with 37 CFR 3.28 and 3.31 is included.
13. [ ] A FIRST preliminary amendment.
    [ ] A SECOND or SUBSEQUENT preliminary amendment.
14. [ ] A substitute specification.
15. [X] A change of power of attorney and/or address letter.
16. [X] Other items or information:

List and Copies of Prior Art References
International Search Report
International Publication No. W098/56185
Internatinal Preliminary Examination Report w/translation thereof
Figs. 1-17

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U.S. APPLICATION NO (If known, see 37 CFR 1.5)	INTERNATIONAL APPLICATION NO	ATTORNEY'S DOCKET NUMBER
09/445088	PCT/JP98/02435	520.37902X00

17. [X] The following fees are submitted:

BASIC NATIONAL FEE (37 CFR 1.492 (a) (1) - (5))

Neither international preliminary examination fee (37 CFR 1.482) nor international search fee (37 CFR 1.445(a)(2)) paid to USPTO and International Search Report not prepared by the EPO or JPO **$970.00**

International preliminary examination fee (37 CFR 1.482) not paid to USPTO but International Search Report prepared by the EPO or JPO **$840.00**

International preliminary examination fee (37 CFR 1.482) not paid to USPTO but international search fee (37 CFR 1.445(a)(2)) paid to USPTO **$760.00**

International preliminary examination fee paid to USPTO (37 CFR 1.482) but all claims did not satisfy provisions of PCT Article 33(1)-(4) **$670.00**

International preliminary examination fee paid to USPTO (37 CFR 1.482) and all claims satisfied provisions of PCT Article 33(1)-(4) **$96.00**

CALCULATIONS PTO USE ONLY		
ENTER APPROPRIATE BASIC FEE AMOUNT =	$ 840.00	
Surcharge of **$130.00** for furnishing the oath or declaration later than [ ] 20 [ ] 30 months from the earliest claimed priority date (37 CFR 1.492(c)).	$ 0.00	

CLAIMS	NUMBER FILED	NUMBER EXTRA	RATE		
Total claims	52 -20 =	47	X $18.00	$ 846.00	
Independent claims	4 -3 =	1	X $78.00	$ 78.00	
MULTIPLE DEPENDENT CLAIM(S) (if applicable)			+$260.00	$ 260.00	
TOTAL OF ABOVE CALCULATIONS =				$ 2,024.00	
Reduction of 1/2 for filing by small entity, if applicable. A Small Entity Statement must also by filed (Note 37 CFR 1.9, 1.27, 1.28).				$ 0.00	
SUBTOTAL =				$ 2,024.00	
Processing fee of **$130.00** for furnishing the English translation later than [ ] 20 [ ] 30 months from the earliest claimed priority date (37 CFR 1.492(f)). +				$ 0.00	
TOTAL NATIONAL FEE =				$ 2,024.00	
Fee for recording the enclosed assignment (37 CFR 1.21(h)). The assignment must be accompanied by an appropriate cover sheet (37 CFR 3.28, 3.31). **$40.00** per property +				$ 40.00	
TOTAL FEES ENCLOSED =				$ 2064.00	
				Amount to be: refunded	$
				charged	$

a. [X] A check in the amount of $ 2,064.00 to cover the above fees is enclosed.

b. [ ] Please charge my Deposit Account No. _____ m the amount of $_____ to cover the above fees. A duplicate copy of this sheet is enclosed.

c. [X] The Commissioner is hereby authorized to charge any additional fees which may be required, or credit any overpayment to Deposit Account No. 01-2135 A duplicate copy of this sheet is enclosed.

NOTE: Where an appropriate time limit under 37 CFR 1.494 or 1.495 has not been met, a petition to revive (37 CFR 1.137(a) or (b)) must be filed and granted to restore the application to pending status.

SEND ALL CORRESPONDENCE TO

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29,621
REGISTRATION NUMBER

09/445088
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13/PRTS

TITLE OF THE INVENTION

IMAGE ENCODING AND DECODING METHOD AND DEVICE

BACKGROUND OF THE INVENTION

Field of the Invention:

This invention relates to an image encoding and decoding method, image encoding and decoding device, and more specifically, to a method of synthesizing interframe predicted images by calculating motion vectors of pixels in an image, by performing interpolation/extrapolation of motion vectors of representative points.

Background of the Invention:

In high efficiency encoding of a moving image, it is known that interframe prediction (motion compensation) which uses similarities between frames produced at different times has a major effect on data compression. The motion compensating system that has become the mainstream of current image encoding technique is the block matching scheme adopted in H.261, MPEG 1 and MPEG 2 which are the international standards for moving image coding. In this system, the image to be encoded is divided into a large number of blocks, and motion vectors are calculated for each block.

Block matching is currently the most widely used compensation technique, but when the whole image

is enlarged, reduced or rotated, motion vectors have to be transmitted for all blocks so the coding efficiency is poor. To deal with this problem, global motion compensation has been proposed wherein the motion vectors of the whole image are represented by a smaller number of parameters (e.g. M. Hotter, "Differential estimation of the global motion parameters zoom and pan", Signal Processing, vol. 16, no. 3, pp. 249-265, Mar. 1989). In this system, the motion vector (ug(x,y), vg(x,y)) of a pixel (x, y) is expressed in the form:

$$u_g(x,y) = a_0 x + a_1 y + a_2$$
$$v_g(x,y) = a_3 x + a_4 y + a_5$$
.....(1)

or

$$u_g(x,y) = b_0 xy + b_1 x + b_2 y + b_3$$
$$v_g(x,y) = b_4 xy + b_5 x + b_6 y + b_7$$
.....(2)

and motion compensation is performed using this motion vector. Herein, a0-a5, b0-b7 are the motion parameters. When motion compensation is performed, the predicted image on the transmitting side and receiving side must be the same. For this purpose, the transmitting side can transmit the values of a0-a5 and b0-b7 directly to the transmitting side, however the motion vectors of

plural representative points may be transmitted instead. Assume that the coordinates of pixels at the upper left, upper right, lower left and lower right corners of an image are respectively (0,0), (r,0), (0,s), (r,s) where r and s are positive integers. If the horizontal and vertical components of the motion vectors of the representative points (0,0), (r,0), (0,s) are respectively (ua,va), (ub,vb), (uc,vc), equation (1) may be rewritten as:

$$u_g(x,y)=\frac{u_b-u_a}{r}x+\frac{u_c-u_a}{s}y+u_a$$
$$v_g(x,y)=\frac{v_b-v_a}{r}x+\frac{v_c-v_a}{s}y+v_a$$
.....(3)

This means that the same functions can be achieved by transmitting ua, va, ub, vb, uc, vc, instead of a0-a5. In the same way, using the horizontal and vertical components (ua,va), (ub,vb), (uc,vc), (ud,vd) of the motion vectors of the four representative points (0,0), (r,0), (0,s), (r,s), equation (2) may be rewritten as:

$$u_g(x,y)=\frac{s-y}{s}\left(\frac{r-x}{r}u_a+\frac{x}{r}u_b\right)+\frac{y}{s}\left(\frac{r-x}{r}u_c+\frac{x}{r}u_d\right)$$

$$=\frac{u_a-u_b-u_c+u_d}{rs}xy+\frac{-u_a+u_b}{r}x+\frac{-u_a+u_c}{s}y+u_a$$

$$v_g(x,y)=\frac{v_a-v_b-v_c+v_d}{rs}xy+\frac{-v_a+v_b}{r}x+\frac{-v_a+v_c}{s}y+v_a$$

.....(4)

Therefore, the same functions can be achieved by transmitting ua, va, ub, vb, uc, vc, ud, vd instead of b0-b7. This situation is shown by Fig. 1. If global motion compensation is performed between an original image 102 and a reference image 101 in the current frame, motion vectors 107, 108, 109, 110 of representative points 103, 104, 105, 106 (wherein motion vectors are defined as starting at points in the original image and terminating at corresponding points in the reference image of the current frame), may be transmitted instead of the motion parameters. In this specification, the system using equation (1) is referred to as global motion compensation based on linear interpolation/extrapolation, and the system using equation (2) is referred to as global motion compensation based on bilinear interpolation/extrapolation.

Warping prediction is the application of this global movement compensation processing to a smaller area of the image. An example of warping prediction using bilinear interpolation/extrapolation is shown in

Fig. 2. Fig. 2 shows processing to synthesize a predicted image of an original image 202 of a current frame using a reference image 201. First, the original frame image 202 is divided into plural polygon-shaped patches to give a patched image 209. The apex of a patch is referred to as a lattice point, and each lattice point is common to plural patches. For example, a patch 210 comprises lattice points 211, 212, 213, 214, and these lattice points are also the apices of other patches. After dividing the image into plural patches in this way, motion estimation is performed. In the example shown here, motion estimation is performed on lattice points using the reference image 201. As a result, each patch in a reference image 203 obtained after motion estimation is transformed. For example, the patch 210 corresponds to a transformed patch 204. This is because, in motion estimation, it was estimated that the lattice points 205, 206, 207, 208 corresponded to 211, 212, 213, 214.

The motion vectors of the lattice points are thereby found, and an interframe predicted image is synthesized by calculating the motion vector for each pixel in the patch by bilinear interpolation. The processing of this warping prediction is basically the same as the global motion compensation shown in Fig. 1, and the "motion vectors at the corners of the image" are transformed into "motion vectors of the lattice points". If a triangular patch is used instead of a

rectangular patch, warping prediction may be realized by linear interpolation/extrapolation.

Examples of encoding and decoding techniques to simplify global motion compensation for representing motion vectors of the whole image using a small number of parameters may be found in the applicant's inventions "Image Encoding and Decoding Methods" (Japanese Unexamined Patent Publication: Application No. Hei 8-60572) and "Methods of Synthesizing Interframe predicted images" (Japanese Unexamined Patent Publication: Application No. Hei 8-249601).

By introducing global motion compensation or warping prediction described above, the motion of the image can be expressed with fewer parameters, and a high data compression rate can be achieved. However, the processing amount in encoding and decoding is greater than in the conventional method. In particular, the divisions of equations (3) and (4) are major factors in making the processing complex. In other words, in global motion compensation or warping prediction, a problem arises in that the processing amount required to synthesize predicted images is large.

SUMMARY OF THE INVENTION

It is therefore an object of this invention to reduce the computing amount by replacing the divisions involved in motion compensation encoding and decoding by a binary shift computation using registers with a small number of bits.

In order to achieve the aforesaid objective, this invention provides an image encoding and decoding method for synthesizing an interframe predicted image by global motion compensation or warping prediction wherein global motion vectors are found by applying a two-stage interpolation/extrapolation to motion vectors of plural representative points having a spatial interval with a characteristic feature. More specifically, this invention provides a method of synthesizing an interframe predicted image wherein, when the motion vector of a pixel is calculated by performing bilinear interpolation/extrapolation on motion vectors of four representative points of an image where the pixel sampling interval in both the horizontal and vertical directions is 1 and the horizontal and vertical coordinates of the sampling points are obtained by adding tointegers (where w=wn/wd, wn is a non-negative integer, wd is the hw power of 2, hw is a non-negative integer and wn<wd), there are representative points at coordinates (i,j), (i+p, j), (i, j+q), (i+p, j+q) (where i, j, p, q are integers), the horizontal and vertical components of the motion vectors of representative points take the values of integral multiples of 1/k (where k is the hk power of 2, and hk is a non-negative integer), and when the motion vector of a pixel at the coordinates (x+w, y+w) is

found, the horizontal and vertical components of the motion vector at the coordinates (x+w, j) are found by linear interpolation/extrapolation of motion vectors of representative points at coordinates (i, j), (i+p, j), as values which are respectively integral multiples of 1/z (where z is the hz power of 2, and hz is a non-negative integer), and after finding the horizontal and vertical components of the motion vector at the coordinates (x+w, j+q) by linear interpolation/extrapolation of motion vectors of representative points at coordinates (i, j+q), (i+p, j+q), as values which are respectively integral multiples of 1/z (where z is the hz power of 2, and hz is a non-negative integer), the horizontal and vertical components of the motion vector of the pixel at the coordinates (x+w, y+w) are found by linear interpolation/extrapolation of the aforesaid two motion vectors at the coordinates (x+w, j), (x+w, j+p) as values which are respectively integral multiples of 1/m (where m is the hm power of 2, and hm is a non-negative integer).

This invention makes it possible to perform divisions by means of shift computations by appropriately selecting representative point coordinates, and to implement the aforesaid motion compensation scheme using registers having a small number of bits by reducing the number of shift bits in the shift computations.

BRIEF DESCRIPTION OF THE DRAWINGS:

Fig. 1 is a diagram showing an example of global mtion compensation for transmitting motion vectors of representative points.

Fig. 2 is a diagram showing an example of warping prediction.

Fig. 3 is a diagram showing an example of the position of representative points for performing high speed processing.

Fig. 4 is a diagram showing a typical construction of a software image encoding device.

Fig. 5 is a diagram showing a typical construction of the software image decoding device.

Fig. 6 is a diagram showing a typical construction of an image encoding device according to this invention.

Fig. 7 is a diagram showing a typical construction of the image encoding device according to this invention.

Fig. 8 is a diagram showing a typical construction of a motion compensation processor 616 of Fig. 6.

Fig. 9 is a diagram showing another typical construction of the motion compensation processor 616 of Fig. 6.

Fig. 10 is a diagram showing a typical construction of a predicted image synthesizer 711 of Fig. 7.

Fig. 11 is a diagram showing a typical construction of a predicted image synthesizer 1103 of Fig. 9.

Fig. 12 is a diagram showing a typical construction of a global motion compensation predicted image synthesizer.

Fig. 13 is a diagram showing an example of a processing flowchart in the software image encoding device.

Fig. 14 is a diagram showing an example of a motion compensation processing flowchart in the software image encoding device.

Fig. 15 is a diagram showing an example of a processing flowchart in the software image decoding device.

Fig. 16 is a diagram showing an example of a predicted image synthesis flowchart in the software image decoding device.

Fig. 17 is a diagram showing a specific example of a device using image encoding/decoding which synthesizes a global motion compensation predicted image by two-stage processing.

Preferred Embodiments of the Invention:

This invention is an application of an invention relating to a method of accelerating the computation involved in global motion compensation and warping prediction already proposed by the applicant (Application No. Hei 08-060572 and Application No. Hei 08-249601). This invention will be described in the context of its application to global motion compensation, but it may also be applied to warping prediction wherein identical processing to that of global motion compensation is performed.

In the following description, it will be assumed that the pixel sampling interval is 1 in both the horizontal and vertical directions and a pixel exists at a point where horizontal and vertical coordinate is obtained by adding w (where w=wn/wd, wn is an integer which cannot be negative, wd is a positive integer and wn<wd) to integers w represents the coordinate phase shift the coordinates of a representative point in global motion compensation, and a pixel. Typically it has the values 0, 1/2, 1/4. Further, it will be assumed that the numbers of pixels of the image in the horizontal and vertical directions are respectively r and s (where r and s are positive integers), and image pixels lie in a range such that the horizontal coordinate is from 0 to less than r, and the vertical coordinate is from 0 to less than s.

When motion compensation is performed using linear interpolation/extrapolation (affine

transformation) or bilinear interpolation/extrapolation (co-1st order transformation), and quantization is performed on the motion vector of each pixel, mismatches are prevented and computations are simplified (Japanese Unexamined Patent Publication: Application No. Hei 06-193970). Hereafter, it will be assumed that the horizontal component and vertical component of the motion vector of a pixel are integral multiples 1/m (where m is a positive integer). It will moreover be assumed that the global motion compensation used for motion vectors of representative points described in "Background of the Invention" will be performed, and that the motion vectors of representative points are integral multiples of 1/k (where k is a positive integer). In this specification, the term "motion vector of a pixel" implies a motion vector used in order to actually synthesize a predicted image when performing global motion compensation.

On the other hand, the term "motion vector of a representative point" means a parameter used to calculate a motion vector of pixel. Therefore, it may occur that the motion vector of a pixel and the motion vector of a representative point do not coincide even if they are located at the same coordinates due to differences of quantization step size, etc.

First, global motion compensation using linear interpolation/extrapolation will be described referring to Fig. 3. In this example, instead of taking a

representative point situated at the corner 301 of the image, representative points 302, 303, 304, 305 are generalized at (i, j) (i+p, j) (i, j+q) (i+p, j+q) (where i, j, p, q are integers). The points 302, 303, 304, 305 may be situated inside or outside the image. If the horizontal and vertical components of the motion vectors of representative points multiplied by k are respectively (u0,v0), (u1,v1), (u2,v2), (u3,v3) (where u0, v0, u1, v1, u2, v2, u3, v3 are integers), the values obtained by multiplying the horizontal and vertical components of a motion vector of a pixel situated at (x+w, y+w) by m, i.e., (u(x+w, y+w), v(x+w, y+w)), may be expressed by the following equation when w=0:

$$
\begin{aligned}
u(x+w,y+w) &= u(x,y) \\
&= (((j+q-y)((i+p-x)u_0+(x-i)u_1) \\
&\quad +(y-j)((i+p-x)u_2+(x-i)u_3))m)//(pqk) \\
v(x+w,y+w) &= v(x,y) \\
&= (((j+q-y)((i+p-x)v_0+(x-i)v_1) \\
&\quad +(y-j)((i+p-x)v_2+(x-i)v_3))m)//(pqk) \\
&\quad \text{.....(5)}
\end{aligned}
$$

where x, y, u(x,y), v(x,y) are integers, [//] is a division which rounds up the result of an ordinary computation to the nearest integer when the result is not an integer, and the order of priority as an operator is equivalent to multiplication and division. It is desirable to round off non-integral

values to the nearest integer so as to minimize computing errors. In this regard, there are three methods of rounding up the sum of 1/2 and an integer, i.e.:

(1) round the value down to the next lowest integer,

(2) round the value up to the next highest integer,

(3) round the value down when the dividend is negative, and round the value up when the dividend is positive (assuming the divisor is always positive).

(4) round the value up when the dividend is negative, and round the value down when the dividend is positive (assuming the divisor is always positive).

In (3) and (4), the direction of rounding does not change depending on whether the dividend is positive or negative, and these methods therefore offer an advantage from the viewpoint of processing amount to the extent that it is unnecessary to determine positive or negative. High speed processing using (3) can be performed using for example the following equation (6).

$$
\begin{aligned}
u(x+w, y+w) &= u(x,y) \\
&= (Lpqk + ((j+q-y)((i+p-x)u_0 + (x-i)u_1) \\
&\quad +(y-j)((i+p-x)u_2 + (x-i)u_3))m + ((pqk)\#2)) \\
&\quad \#(pqk) - L \\
v(x+w, y+w) &= v(x,y) \\
&= (Mpqk + ((j+q-y)((i+p-x)v_0 + (x-i)v_1) \\
&\quad +(y-j)((i+p-x)v_2 + (x-i)v_3))m + ((pqk)\#2)) \\
&\quad \#(pqk) - M \\
&\quad \ldots\ldots\ldots (6)
\end{aligned}
$$

where "#" is an integer division wherein digits after the decimal point are discarded, and the order of priority of computation is assumed to be the same as that of multiplication and division. Generally, this is the type of division that can be realized most easily by a computer. L and M are numbers for ensuring that the dividend is always positive, and are positive integers which are sufficiently large. The term (pqk#2) is used to round off the division result to the nearest integer.

Processing in terms of integers in itself contributes to reducing the amount of processing. However, if p, q, k are respectively set equal to the α, β, hk power of 2 (where α, β, hk are non-negative integers), the calculation of equation (5) can be performed by a shift computation of $\alpha+\beta+hk$ bits, and the amount of processing performed by the computer and special hardware can be largely reduced. If m is set equal to the hm power of 2 (where hm is a non-negative integer, and $hm<\alpha+\beta+hk$, equation (6) may be written as:

$$
\begin{aligned}
u(x+w, y+w) &= u(x, y) \\
&= ((2L+1)\langle\langle((\alpha+\beta+h_k-h_m-1) \\
&+(j+q-y)((i+p-x)u_0+(x-i)u_1) \\
&+(y-j)((i+p-x)u_2+(x-i)u_3)) \\
&\rangle\rangle(\alpha+\beta+h_k-h_m)-L \\
v(x+w, y+w) &= v(x, y) \\
&= ((2M+1)\langle\langle((\alpha+\beta+h_k-h_m-1) \\
&+(j+q-y)((i+p-x)v_0+(x-i)v_1) \\
&+(y-j)((i+p-x)v_2+(x-i)v_3)) \\
&\rangle\rangle(\alpha+\beta+h_k-h_m)-M \\
&\text{.....(7)}
\end{aligned}
$$

((x<<α) means that x is shifted by α bits to the left, and 0 is set in the lower α bits. (x>>α) means that x is shifted by α bits to the right, and 0 is set in the upper α bits. The order of priority of these operators is intermediate between addition/subtraction and multiplication/division). Therefore the number of shift bits may be written as $\alpha+\beta$+hk-hm.

When w is not 0, according to the definition w=wn/wd, equation (5) may be rewritten by the following equation (8):

$$u(x+w,y+w)=u(x+\frac{w_d}{w_n},y+\frac{w_d}{w_n})$$
$$=(((w_dj+w_dq-w_dy-wn)((w_di+w_dp-w_dx-w_n)u_0$$
$$+(w_dx+w_n-w_di)u_1)$$
$$+(w_dy+w_n-w_dj)((w_di+w_dp-w_dx-w_n)u_2$$
$$+(w_dx+w_n-w_di)u_3))m)$$
$$//(w_d{}^2pqk)$$
$$v(x+w,y+w)=v(x+\frac{w_d}{w_n},y+\frac{w_d}{w_n})$$
$$=(((w_dj+w_dq-w_dy-w_n)((w_di+w_dp-w_dx-w_n)v_0$$
$$+(w_dx+w_n-w_di)v_1)$$
$$+(w_dy+w_n-w_dj)((w_di+w_dp-w_dx-w_n)v_2$$
$$+(w_dx+w_n-w_di)v_3))m)$$
$$//(w_d{}^2pqk)$$

.....(8)

If wd is the hw power of 2 and hw is a non-negative integer, the division by(p.q.k.wd.wd) becomes a shift computation of $\alpha+\beta$+hk+2hw bits, and the division may therefore be replaced by a shift computation as in the case of w=0. Also as in the case of equation (7), if hm< $\alpha+\beta$+hk+2hw, the number of shift bits can be reduced to $\alpha+\beta$+hk+2hw-hm bits by dividing both the numerator and denominator by m. Therefore, provided that wd is a hw power of 2, the processing when w=0 and when w≠0 is basically the same. Hereafter, although the equations are somewhat complex, the case w≠0 will be described. To find the calculation results for w=0, the substitutions wn=0, wd=1, hw=0 may be made.

To obtain the same global motion compensation predicted image on the transmitting and receiving sides, information about motion vectors of representative points must be transmitted to the receiving side in some form or other. In one method, the motion vectors of representative points are transmitted without modification, and in another method, the motion vectors of the corners of the image are transmitted and the motion vectors of representative points are calculated from these values. Hereafter, the latter method is described.

Assume that the motion vectors of the four corners (-c, -c), (r-c, -c) (-c, s-c), (r-c, s-c) of the image can be only integral multiples of 1/n (where n is a positive integer, c=cn/cd, cn is a non-negative integer, cd is a positive integer and cn<cd), and that (u00, v00), (u01, v01), (u02, v02), (u03, v03) which are the horizontal and vertical components of these vectors multiplied by n, are transmitted as global motion parameters. c represents a phase shift between the corners and representative points, and it typically has a value of 0, 1/2 or 1/4. (u0, v0), (u1, v1), (u2, v2), and(u3, v3) which are the horizontal and vertical components of the motion vectors respectively at the points (i, j), (i+p, j), (i, j+q),and (i+p, j+q) multiplied by k, may be defined as:

$$u_0 = u'(i, j)$$
$$v_0 = v'(i, j)$$
$$u_1 = u'(i + p, j)$$
$$v_1 = v'(i + p, j)$$
$$u_2 = u'(i, j + q)$$
$$v_2 = v'(i, j + q)$$
$$u_3 = u'(i + p, j + q)$$
$$v_3 = v'(i + p, j + q)$$
.....(9)

where u'(x, y), v'(x, y) are defined by transforming equation (5):

$$u'(x,y) = (((c_d s - c_n - c_d y)((c_d r - c_n - c_d x)u_{00} + (c_d x + c_n)u_{01} + (c_d y + c_n)((c_d r - c_n - c_d x)u_{02} + (c_d x + c_n)u_{03}))k) /// (c_d{}^2 rsn)$$
$$v'(x,y) = (((c_d s - c_n - c_d y)((c_d r - c_n - c_d x)v_{00} + (c_d x + c_n)v_{01}) + (c_d y + c_n)((c_d r - c_n - c_d x)v_{02} + (c_d x + c_n)v_{03}))k) /// (c_d{}^2 rsn)$$
.....(10)

[///] is a division wherein the computation result is rounded to the nearest integer when the result of an ordinary division is not an integer, and the order of priority is equivalent to multiplication and division. In this way, if (u0, v0), (u1, v1), (u2, v2), and (u3, v3) are calculated and global motion compensation is performed at the representative points (i, j), (i+p, j), (i, j+q), and (i+p, j+q), global

motion compensation at the representative points (-c, -c), (r-c, -c) (-c, s-c), and (r-c, s-c) can be approximated. As described hereabove, if p and q are non-negative integral powers of 2, the processing can be simplified. In general, it is preferable not to perform extrapolation when calculating motion vectors of pixels in the image by equation (5). This is to avoid increase of quantization error in motion vectors of representative points due to extrapolation. For this reason, it is desirable that all the representative points are in such positions that they surround the pixels in the image. Hence when i=j=c=0, it is appropriate that p and q are effectively the same as, or have slightly larger values than, r and s. Care must however be exercised as if the values of p and q are too large, the number of bits required for the calculation increases.

To reduce computational error in the processing of equations (9) and (10), it is preferable that [///] rounds off non-integral values to the nearest integer. In this regard, the sum of 1/2 and an integer may be rounded off to the nearest integer by any of the aforesaid methods (1)-(4). However compared to the case of equation (5) (calculation performed for each pixel), equation (14) requires fewer computations (only four calculations for one image), so even when the methods of equations (1) or (2) are chosen, there is not much effect on the total computational amount.

If the values of p and q are set to non-negative integral powers of 2 as described in the above examples, the synthesis of interframe predicted images in global motion compensation is greatly simplified. However, there is still one other problem. Considering for example the case p=512, q=512, k=32, m=16, wd=2, wn=1 (w=0.5), which are typical parameters in image coding, we have $\alpha+\beta+hk+2hw-hm=21$. This means that when u(x+w, y+w) is a value requiring 12 or more bits in binary form, a register of at least 33 bits is required to perform the high speed computation of equation (8). When for example m=16, the value of u(x+w, y+w) is obtained by multiplying the horizontal component of the real motion vector by 16, so this could well be a value requiring 12 or more bits in binary form. At the present time, few processors have registers capable of storing integers of 33 or more bits, and they are expected to remain costly in future. Moreover in general, if the processor circuit is large, power consumption is correspondingly greater, so an algorithm requiring a large register is also disadvantageous from the viewpoint of power consumption. Therefore it is desirable that even when the division can be replaced by a shift computation, the number of shift bits is as small as possible.

To resolve this problem, the two-step algorithm according to this invention which is described below may be used. Prior to calculating the motion vector of

the pixel at the point (x+w, y+w) using the motion vectors of the representative points (i, j), (i+p, j), (i, j+q), (i+p, j+q), motion vectors at provisional representative points (i, y+w) and (i+p, y+w) are calculated so that the horizontal and vertical components are integral multiples of 1/z (where z is a positive integer). As in the aforesaid example, the horizontal and vertical components of the motion vectors of the representative points (i, j), (i+p, j), (i, j+q), (i+p, j+q) multiplied by k are taken to be respectively (u0, v0), (u1, v1), (u2, v2), (u3, v3) (where u0, v0, u1, v1, u2, v2, u3, v3 are integers). If the provisional representative points are situated at (i, y+w) and (i+p, y+w), (uL(y+w), vL(y+w)) and (uR(y+w), vR(y+w)) which are the horizontal and vertical components of the motion vectors of these provisional representative points multiplied by z, are defined as follows:

$$u_L(y+w) = (((w_d j + w_d q - w_d y - w_n)u_0 + (w_d y + w_n - w_d j)u_2)z)///(w_d qk)$$
$$v_L(y+w) = (((w_d j + w_d q - w_d y - w_n)v_0 + (w_d y + w_n - w_d j)v_2)z)///(w_d qk)$$
$$u_R(y+w) = (((w_d j + w_d q - w_d y - w_n)u_1 + (w_d y + w_n - w_d j)u_3)z)///(w_d qk)$$
$$v_R(y+w) = (((w_d j + w_d q - w_d y - w_n)v_1 + (w_d y + w_n - w_d j)v_3)z)///(w_d qk)$$
.....(11)

[////] is a division which rounds up the result of an ordinary computation to the nearest integer when the result is not an integer, and the order of priority is equivalent to multiplication and division. (The required function for [////] is the same as the [///] described above). As (i, y+w) lies on a line joining (i, j) and (i, j+q), (uL(y+w), vL(y+w)) can easily be found by a first order linear intrapolation/extrapolation using (u0, v0) and (u2, v2). Likewise, as (i+p, y+w) lies on a line joining (i+p, j) and (i+p, j+q) may also be found by a first order linear interpolation/extrapolation.

By performing another first order linear interpolation/extrapolation on the motion vectors (uL(y+w), vL(y+w)) and (uR(y+w), vR(y+w)) of the provisional representative points found as described above, (u(x+w, y+w), v(x+w, y+w)) which are the horizontal and vertical components of the motion vector of the pixel at (x+w, y+w) multiplied by m, are found. This processing is performed by the following equation:

$$u(x+w,y+w)=(((w_d i+w_d p-w_d x-w_n)u_L(y+w)+(w_d x+w_n-w_d i)u_R(y+w))m)//(w_d pz)$$
$$v(x+w,y+w)=(((w_d i+w_d p-w_d x-w_n)v_L(y+w)+(w_d x+w_n-w_d i)v_R(y+w))m)//(w_d pz)$$
.....(12)

In the same way as described above, if p is the α power of 2, m is the hm power of 2, z is the hz power of 2, wd is the hw power of 2 (where α, hm, hz, ws are non-negative integers), the division by p.z.wd in equation (12) may be replaced by α+hz+hwhm bit right shift (where hm< α+hz+hw). Also, if z=16 (hz=4), and the typical parameters p=512, q=512, k=32, m=16, wd=2, wn=1 (w=0.5) are used, the number of shift bits is 10, so the number of bits required for the register used in the computation can be largely reduced. It may be noted that in the above example, a motion vector is found by performing a first order linear interpolation/extrapolation in the vertical direction on the motion vector of a representative point, and the motion vector of a pixel is then found by performing a first order linear interpolation/extrapolation in the horizontal direction on the motion vector of this representative point. Conversely, the same result may be obtained by performing a first order linear interpolation/extrapolation in the horizontal direction when the motion vector of a representative point is found, and in the vertical direction when the motion vector of a pixel is found.

In this scheme, the two steps of equations (11) and (12) are required to find a motion vector of a pixel, and at first sight it might appear that this would lead to an increase of computation amount. However if the motion vector of a provisional

representative point is first found, this may be used for all r pixels on a line having the vertical coordinate y+w, so the percentage of the total processing amount due to equation (11) is very small. Therefore, the advantage (i.e. a smaller number of registers) gained by the lesser number of bits outweighs the disadvantage of increased computation amount due to having to perform the calculation of equation (11).

After obtaining the values (u(x+w, y+w), v(x+w, y+w)), (u(x+w, y+w), v(x+w, y+w)) may be divided into integral parts (uI(x+w, y+w), vI(x+w, y+w)) and fractional parts (uF(x+w, y+w), vF(x+w, y+w)) by the following processing.

$$u_1(x+w, y+w) = ((Lm + u(x+w, y+w)) \rangle\rangle h_m) - L$$
$$v_1(x+w, y+w) = ((Mm + v(x+w, y+w)) \rangle\rangle h_m) - M$$
.....(13)

$$u_F(x+w, y+w) = u(x+w, y+w) - u_1(x+w, y+w)m$$
$$v_F(x+w, y+w) = v(x+w, y+w) - v_1(x+w, y+w)m$$
.....(14)

where uI(x+w, y+w), vI(x+w, y+w) are integers expressing the integral parts of a motion vector of a pixel. uF(x+w, y+w), vF(x+w, y+w) are integers both having values from 0 to less than m expressing m times the fractional parts of a motion vector of a pixel. As

in the above example, m is the hm power of 2 (where hm is a non-negative integer), and L and M are sufficiently large to make the shift values non-negative.

When bilinear order interpolation is used as a method of interpolating luminance value, the luminance value of a pixel in the interframe predicted image can also be found by the following processing. When x' = x+w+uI (x+w, y+w), y' = y+w+vI (x+w, y+w), if the luminance values of pixels at (x', y'), (x'+1, y'), (x', y'+1), (x'+1, y'+1) in the reference image are Ya, Yb, Yc, Yd, the luminance value Y (x+w, y+w) of a pixel at the point (x+w, y+w) in the interframe predicted image may be found by:

$$Y(x+w,y+w)=((m-v_F)((m-u_F)Y_a+u_FY_b) +v_F((m-u_F)Y_c+u_FY_d)+(m^2\rangle\rangle 1))\rangle\rangle(2h_m) \quad \text{.....(15)}$$

where uF, vF are respectively abbreviations for uF(x+w, y+w), vF(x+w, y+w).

In equations (12) and (13), α+hz+hw-hm bit and hm bit right shifts are respectively performed. This means that if an (α+hz+hw-hm)+hm=α+hz+hw bit right shift is performed in the calculation of equation (10), uI(x+w, y+w) and vI(x+w, y+w) can be calculated in one step. It is convenient if α+hz+hw is an integral multiple of 8 because, in general, the size of a

processor register is a multiple of 8 bit units. Frequently, two 8 bit registers (an upper bit register and a lower bit register) are linked to make a 16 bit register, or four 8 bit registers or two 16 bit registers are linked to make a 32 bit register. If the values of uI(x+w, y+w), and vI(x+w, y+w) have already been calculated by, for example, a 16 bit shift computation, there is then no need to perform another shift computation. In other words, if the value prior to shift is stored in a 32 bit register, and the upper 16 bits are used as a separate register, the values of uI(x+w, y+w) or vI(x+w, y+w) are stored in this 16 bit register.

It will be appreciated that making the number of shift bits an integral multiple of 8 facilitates not only the processing of equation (10) but all aspects of the shift computation. It is particularly important to make processing easier when a large number of shift computations has to be performed (e.g. a shift computation for each pixel). Also, by first adding the same number of left shifts as the number of bits to the numerator and denominator, the number of right shifts due to division can be increased even when the number of shift bits is not an integral multiple of 8. For example, when a computation is performed by a 6 bit right shift, the same computation can be performed by an 8 bit right shift by first multiplying the value to which the shift operation is applied by 4 (this is

equivalent to performing a 2 bit left shift). (Taking equation (5) which concerns u(x+w, y+w) as an example, this processing can be implemented by first multiplying u0, u1, u2, u3 by 4). Care must however be taken when performing this processing that overflow of the value to be shifted does not occur.

Many image encoders and decoders are able to adapt to a plurality of image sizes. In this case, when for example global motion compensation is performed using equations (12), (13), (14), the number of shift bits changes according to change of image size and can no longer be fixed to integral multiples of 8. This can be treated as follows. For example, consider the situation where an α+hz+hw bit right shift is required to calculate uI(x+w, y+w) and vI(x+w, y+w) as described above, where α can have a value in the range 7-11. If hz=5, hw=1 when α is less than 10, and hz=4, hw=1 when α=11, the number of shift bits can be arranged to be always 16 or less. As stated hereintofore, when the number of shift bits is less than 16, it can be simulated to be 16 by first multiplying the value to be shifted by a constant. Hence, when the image size changes, the number of shift bits can be controlled to a convenient number by varying other parameters (e.g. quantization step size of motion vectors) accordingly. Care must be taken however not to make the quantization step size of the

motion vectors so large that it causes an appreciable degradation of the decoded image.

When the algorithm shown in this specification is applied to ordinary global motion compensation, the motion vector of a representative point is first found to a precision of 1/k pixels using the motion vectors of the corners of the image which have a precision of 1/n pixels. Next, the motion vector of a provisional representative point is found to a precision of 1/z pixels using the motion vector of the representative point, and the motion vector of a pixel is found to a precision of 1/m pixels using the motion vector of this provisional representative point. When the motion vectors of the corners of the image are transmitted as a motion parameter, it is desirable to make k as large a value as possible in order to closely approximate bilinear interpolation/extrapolation by this parameter. However, the horizontal and vertical components of the motion vector of the representative point includes an error having an absolute value equal to or less than 1/(2k) due to the effect of quantization. From the viewpoint of making the approximation more accurate, it is preferable to increase the precision of the motion vector also of the provisional representative point, however since the motion vector of the provisional representative point is found using the motion vector of the representative point, there is no advantage to be gained in calculating it with an accuracy greater

than that of the motion vector of the representative point. Therefore, it is preferable that $z \leq k$ in order to suppress the number of bits required for the computation, and that $m \leq z$ for the same reason.

The above discussion has considered global motion compensation using bilinear interpolation/extrapolation, but the number of shift bits can be suppressed by introducing the same processing in the case of linear interpolation/extrapolation. For example, assume that the horizontal and vertical components of the motion vectors of representative points at (i, j), (i+p, j), and (i, j+q) (where i, j, p, q are integers) multiplied by k, are (u0, v0), (u1, v1), and (u2, v2) (where u0, v0, u1, v1, u2, v2 are integers). The horizontal and vertical components of the motion vectors of a pixel (x+w, y+w) multiplied by m, i.e. (u(x+w, y+w), v(x+w, y+w)), can then be expressed as follows (where x, y, u(x+w, y+w), v(x+w, y+w) are integers and the definition of w is the same as above).

$$
\begin{aligned}
u(x+w, y+w) = (((u_1 - u_0)(w_d x + w_n - w_d i)q \\
&+(u_2 - u_0)(w_d y + w_n - w_d j)p + u_0 w_d pq)m) \\
&//(w_d pqk) \\
v(x+w, y+w) = (((v_1 - v_0)(w_d x + w_n - w_d i)q \\
&+(v_2 - v_0)(w_d y + w_n - w_d j)p + v_0 w_d pq)m) \\
&//(w_d pqk)
\end{aligned}
\qquad \text{.....(16)}
$$

In this case also, p, q, k, m, wd are respectively α, β, hk, hm and hw powers of 2 (where α, β, hk, hm and hw are non-negative integers), and if $\alpha \geq \beta$, this equation may be rewritten as:

$$u+(x+x,y+x) = (((u_1-u_0)(w_d x + w_n - w_d i)2^{\alpha-\beta} + (u_2-u_0)(w_d y + w_n - w_d j) + u_0 w_d p)m) / /(w_d pk)$$
$$v(x+w,y+w) = (((v_1-v_0)(w_d x + w_n - w_d i)2^{\alpha-\beta} + (v_2-v_0)(w_d y + w_n - w_d j) + v_0 w_d p)m) / /(w_d pk)$$
.....(17)

As in the case when bilinear interpolation/extrapolation is used, the integer part of the motion vector of the pixel at (x+w, y+w) can be found by an α+hk+hw bit right shift, therefore if α +hk+hw is arranged to be an integral multiple of 8, processing can be simplified for the same reason as given above. It should be noted that when $\alpha < \beta$, the number of shift bits is β+hk+hw.

The construction of the image encoding device and decoding device for performing image encoding and decoding according to this invention which uses the synthesis of interframe predicted images, will now be described.

Fig. 6 shows the configuration of one embodiment of an image encoding device according to this invention.

The construction shown in the diagram is essentially the same as in the prior art encoding device excepting for the motion compensation processor 616.

A subtractor 602 calculates a difference between an input frame (original image of a current frame which is to be encoded) 601 and an output image 613 (interframe predicted image) of an interframe/intraframe coding changeover switch 619, and outputs a differential image 603. This differential image is quantized by a quantizer 605 after converting to DCT coefficients by a DCT converter 604 so as to give quantized DCT coefficients 606. These quantized DCT coefficients are output as transmission information to a transmission path, and are also used to synthesize an interframe predicted image in the encoder.

The procedure for synthesizing the frame predicted image will now be described.

The quantized DCT coefficients 606 pass through an inverse quantizer 608 and inverse DCT converter 609 so as to give a decoded differential image 610 (same image as the differential image reproduced on the receiving side). The output image 613 of the interframe/intraframe coding changeover switch 619 (described later) is added to this in an adder 611, and a decode imaged 612 of the current frame (same image as the decoded image of the current frame reproduced on the receiving side) is thus obtained. This image is

first stored in a frame memory 614, and is delayed by the time for one frame. At this time, therefore, the frame memory 614 outputs a decoded image 615 of the immediately preceding frame. The decoded image of the immediately preceding frame and input image 601 of the current frame are input to a motion compensation processor 616, and the motion compensation processor 616 synthesizes the aforesaid interframe predicted image. The configuration of this point will be described later.

A predicted image 617 is input to the interframe/intraframe coding changeover switch 619 together with a "0" signal 618. This switch changes over between interframe coding and intraframe coding by selecting either of these inputs.

When the predicted image 617 is selected (Fig. 6 shows this case), interframe coding is performed. On the other hand, when a "0" signal is input, the input image is DCT encoded as it is and output to the transmission path, so intraframe coding is performed.

To obtain a correctly decoded image on the receiving side, it is necessary to know whether interframe coding or intraframe coding was performed on the transmitting side. For this purpose, an identifying flag 621 is output to the transmission path. Finally, an H.261 encoded bit stream 623 is obtained by multiplexing the quantized DCT coefficients, motion

vectors and identifying flag information in a multiplexing unit 622.

Fig. 7 shows a typical construction of a decoder 700 for receiving the encoded bit stream output by the encoder of Fig. 6.

A bit stream 717 which is received is split into quantized DCT coefficients 701, motion vectors 702 and intraframe/interframe identifying flag 703 by a demultiplexer 716.

The quantized DCT coefficients 701 pass through an inverse quantizer 704 and inverse DCT converter 705 so as to give a differential image 706. This differential image is added to an output image 715 of an interframe/intraframe coding changeover switch 714 in an adder 707, and the result is then output as a decoded image 708. The interframe/intraframe coding changeover switch changes over the output depending on the interframe/intraframe coding identifying flag 703. The predicted image 712 used when interframe coding is performed is synthesized in a predicted image synthesizer 711. Here, positions are shifted according to the received motion vectors 702 relative to the decoded image 710 of the immediately preceding frame stored in a frame memory 709. In the case of intraframe coding, the interframe/intraframe coding changeover switch merely outputs a "0" signal 713.

Fig. 8 shows a typical construction of the motion compensation processor 616 of the image encoding

device which uses a global motion compensation scheme based on linear interpolation/extrapolation for transmitting motion vectors of representative points. Numbers which are the same as those of Fig. 6 denote the same components. Motion estimation relating to global motion compensation is performed between the decoded image 615 of the immediately preceding frame and the original image 601 of the current frame by the global motion estimating unit 802, and global motion compensation parameters (for example, values of the aforesaid ua, va, ub, vb, uc, vc, ud, vd) are estimated. Information 803 about these values is transmitted as part of motion information 620. A global motion compensation predicted image 804 is synthesized by a global motion compensation predicted image synthesizer 808 using equation (3), and is supplied to a block matching unit 805. Here, motion compensation (motion estimation and predicted image synthesis) by block matching is performed between the global motion compensation predicted image and original image of the current frame, and block motion vector information 806 and a final predicted image 617 are thereby obtained. This motion vector information is multiplexed with motion parameter information in a multiplexer 807, and output as the motion information 620.

Fig. 10 shows a typical construction of the predicted image synthesizer 711 of Fig. 7. Numbers which are the same as those of other diagrams denote

the same components. A global motion compensation predicted image 804 is synthesized in the global motion compensation predicted image synthesizer 808 using the global motion compensation parameters 803 extracted from the motion information 702 in a splitting unit 1002, relative to the decoded image 710 of the immediately preceding frame. The image 804 is supplied to a block matching predicted image synthesizer 1001, and the final predicted image 712 is synthesized using the block matching motion vector information 806 extracted from the motion information 702.

Fig. 9 shows another typical construction of the motion compensation processor 616. Numbers which are the same as those of Fig. 6 denote the same components. In this example, global motion compensation or block matching is applied to each block. Motion compensation is performed between the decoded image 615 of the immediately preceding frame and the original image 601 of the current frame, respectively by global motion compensation in a global motion estimating unit 902 and global motion compensation predicted image synthesizer 911, and by block matching in a block matching unit 905. A selection switch 908 selects the most suitable scheme for every block between a predicted image 903 due to global motion compensation and a predicted image 906 due to block matching. Global motion compensation parameters 904, motion vectors 907 for each block and selection

information 909 relating to global motion compensation/block matching are multiplexed by a multiplexer 910, and the result is output as the motion information 620.

Fig. 11 shows a typical construction of a predicted image synthesizer 1103 of a decoder which decodes the bit stream generated by an image encoding device using a motion compensation processor 901. Numbers which are the same as those of other diagrams denote the same components. The global motion compensation predicted image 903 is synthesized in the global motion compensation predicted image synthesizer 911 using global motion compensation parameters 904 extracted from the motion information 702 in the splitting unit 1002, relative to the decoded image 710 of the immediately preceding frame. The block matching predicted image 906 is synthesized in the block matching predicted image synthesizer 1101 using block matching motion vector information 907 extracted from the motion information 702 relative to the decoded image 710 of the immediately preceding frame. A selection switch 1104 selects either of these schemes for each block, i.e., the predicted image 903 due to global motion compensation or the predicted image 906 due to block matching, based on the selection information 909 extracted from the motion information 702. After this selection process is applied to each block, the final predicted image 712 is synthesized.

Fig. 12 shows the structural configuration of the global motion compensation predicted image synthesizer according to this invention. It will be assumed that the motion vectors of the corners of the compensation image are transmitted as global motion parameters. The motion vectors of representative points are calculated by equations (9), (10) in a computing unit 1205 using information 1204 relating to motion vectors of the corners of the image. Using information 1206 relating to the motion vectors of these representative points, the motion vectors of provisional representative points are calculated for each line using equation (11) in a computing unit 1207. Then, by using information 1208 relating to the motion vectors of these provisional representative points, motion vectors for each pixel are calculated from equation (12) in a computing unit 1209. At the same time, using information 1210 relating to the motion vectors of each pixel and the decoded image 1202 of the immediately preceding frame, a global motion compensation predicted image 1203 is synthesized and output by a processing unit 1211.

In addition to a conventional image encoder or image decoder using a special circuit or chip, this invention may also be applied to a software image encoder or software image decoder using a universal processor.

Fig. 4 and Fig. 5 respectively show examples of a software image encoder 400 and software image decoder 500. In the software encoder 400, an input image 401 is stored in an input frame memory 402, and a universal processor 403 reads and encodes information from the input frame memory 402. The program required for driving the universal processor 403 is read from an storage device 408 comprising a hard disk or floppy disk, etc., and stored in a program memory 404. The universal processor encodes the information by using a processing memory 405. The encoded information output by the universal processor 403 is then stored in an output buffer 406, and output as an encoded bit stream 407.

Fig. 13 shows a flowchart of the encoding software which runs on the software encoder shown in Fig. 4.

First, image encoding is started in a step 1301, and 0 is input to a variable N in a step 1302. Next, if the value of N is 100, in steps 1303, 1304, 0 is input to N. N is a frame number counter which is incremented by 1 whenever processing of one frame is completed, and it can take a value in the range 0-99 when encoding is performed. When the value of N is 0, the frame being encoded is an I frame (motion compensation is not performed, and intraframe coding is performed for all blocks), otherwise it is a P frame (a frame comprising blocks where motion compensation is performed). This

means that if the value of N is 100, one I frame is encoded after 99 P frames were encoded. The optimum value of N varies according to the performance of the encoder and the environment in which the encoder is used. In this example, the value 100 was used, but the value of N is not necessarily limited to 100. The determination and output of frame type (I or P) are performed in a step 1305. When the value of N is 0, 'I' is output as frame type identifying information to the output buffer, and thereafter, the frames wherein coding is performed will be I frames. Herein, the expression "output to output buffer" means that part of the bit stream is output from the encoder to external devices after storing in the output buffer (406 in Fig. 4). When N is not 0, 'P' is output by the output buffer as frame type identifying information, and thereafter, the frames wherein coding is performed will be P frames.

In a step 1306, the input image is stored in a frame memory A. The frame memory A described here denotes part of the memory area of the software encoder (for example, this memory area is reserved in a memory 405 of Fig. 4). In a step 1307, it is determined whether the frame currently being encoded is an I frame. If it is not an I frame, motion estimation/motion compensation is performed in a step 1308.

Fig. 14 shows the detailed processing which is performed in this step 1308. First, global motion

estimation is performed between the images stored in the frame memories A and B (the decoded image of the immediately preceding frame is stored in a frame memory B) in a step 1401, and the motion vectors of the corners of the image are output as global motion parameters by the output buffer. In a step 1402, the motion vectors of representative points are calculated using the motion vectors of the corners of this image by equations (9), (10). Next, in a step 1403, 0 is input to a variable M. M represents the number of lines in the image. When M is 0, it means that the uppermost line of the image is being processed, and when M is a value obtained by subtracting 1 from the number of lines in the image, it means that the lowermost line of the image is being processed. By using the motion vectors of representative points calculated in the step 1402, the motion vectors of provisional representative points on the Mth line are calculated by equation (11) in a step 1404. Then, making use of the motion vectors of these provisional representative points, the motion vectors of all the pixels in the Mth line are calculated by equation (12), and the Mth line of the global motion compensation predicted image is synthesized using the decoded image of the immediately preceding frame which is stored in the frame memory B according to the calculated motion vectors in a step 1405. In a step 1406, 1 is added to the value of M. In a step 1407, if the value of M is

equal to the number of lines in the image, the routine proceeds to a step 1408, and if it is not equal, the routine proceeds to the step 1404. When the processing of the step 1408 starts, the image due to global motion compensation is stored in a frame memory D. In the steps after the step 1408, block matching is performed. First, in the step 1408, motion estimation for every block is performed between the frame memory F and frame memory A (input image), the motion vectors of each block are calculated, and these motion vectors are output to the output buffer. Next, a predicted image is synthesized by block matching in a step 1409 using the motion vectors and the image stored in the frame memory F, and this is stored in a frame memory C as a final predicted image. In a step 1410, a differential image of the frame memories A and C is found, and this is stored in the frame memory A.

Returning now to Fig. 13, immediately before the process in the step 1308 is started, when the current frame is an I frame, the input image is stored in the frame memory A, and when the current frame is a P frame, a differential image between the input image and predicted image is stored in the frame memory A. In the step 1308, DCT is applied to the image stored in this frame memory A, and the DCT coefficients calculated here are output to the output buffer after being quantized. Further, in a step 1310, inverse quantization and inverse DCT are applied to these

quantized DCT coefficients, and the image obtained as a result is stored in the frame memory B. Next, it is again determined whether the current frame is an I frame, and when the image is not an I frame, the images in the frame memories B and C are added in a step 1312, and this result is stored in the frame memory B. Here, the encoding of one frame is finished, and the image stored in the frame memory B immediately before processing of a step 1313 is performed is a reconstracted image of the frame for which encoding has just been completed (same as that obtained on the decoding side). In the step 1313, it is determined whether the frame for which coding is complete is the last frame, and if it is the last frame, coding is terminated. When it is not the last frame, 1 is added to N in a step 1314, the routine returns to the step 1303 again, and encoding of the next frame is started. It will be understood that although the flowchart described here relates to a method of applying block matching to the global motion compensation predicted image synthesized as a result of performing global motion compensation (method corresponding to a device using a motion compensation processor 801 of Fig. 8), a flowchart relating to a method of performing global motion compensation and global matching in parallel (method corresponding to a device using a motion compensation processor 901 of Fig. 9) can be prepared by making a slight modification.

On the other hand, in the software decoder 500, an input encoded bit stream 501 is first stored in an input buffer 502, and read by a universal processor 503. The universal processor 503 decodes the information using a program memory 504 for storing a program read from an storage device 508 comprising a hard disk or floppy disk, etc., and a processing memory 505. The decoded image obtained is then stored in an output frame memory 506, and output as an output image 507.

Fig. 15 shows a flowchart of decoding software which runs on a software decoding device shown in Fig. 5. Processing is started in 1501, and in a step 1502, it is determined whether or not there is input information. Here, if there is no input information, decoding is terminated in a step 1503. When there is input information, frame type information is first input in a step 1504. The term "input" means that information stored in an input buffer 502 is read. In a step 1505, it is determined whether or not the read frame type information is 'I'. When it is not 'I', predicted image synthesis is performed in a step 1506. The details of the processing performed in this step 1506 is shown in Fig. 16.

First, in a step 1601, the motion vectors of the corners of the image are input. In a step 1602, the motion vectors of representative points are calculated by equations (9), (10) using the motion vectors of the corners of this image. Next, in a step

1603, 0 is input to the variable M. M represents the number of lines in the image. When M is zero, it means that the uppermost line of the image is being processed, and when M is a value obtained by subtracting 1 from the number of lines of the image, it means that the lowermost line of the image is being processed. Using the motion vectors of representative points calculated in the step 1602, the motion vectors of provisional representative points on the Mth line are calculated by equation (11) in a step 1604. The motion vectors for all the pixels in the Mth line are calculated by equation (12) in a step 1605. From the calculated motion vectors, the Mth line of the global motion compensation predicted image is synthesized using the decoded image of the immediately preceding frame stored in a frame memory E, and this is stored in a frame memory G. The memory G herein means part of the area of the memory 505 of the software decoder.

In a step 1606, 1 is added to the value of M. If the value of M is equal to the number of lines of the image in a step 1607, the routine proceeds to a step 1608, and if it is not equal, the routine shifts to the step 1604. When the processing of the step 1608 is started, the predicted image due to global motion compensation is stored in the frame memory G. In the step 1608, block matching is performed. Motion vector information for each block is input, the predicted image due to block matching is synthesized using these motion

vectors and the image stored in the frame memory G, and this predicted image is stored in the frame memory D.

Returning to Fig. 15, quantized DCT coefficients are input in a step 1507, and the image obtained by applying inverse quantization and inverse DCT to these is stored in the frame memory E. In a step 1508, it is determined whether or not the frame currently being decoded is an I frame. When it is not an I frame, the images stored in the frame memories D and E are added in a step 1509, and the resulting image is stored in the frame memory E. The image stored in the frame memory E immediately prior to performing the processing of the step 1510 is the reproduced image. In the step 1510, the image stored by this frame memory E is output to the output frame memory 506, and output from the decoder as an output image without modification. When decoding of one frame is completed in this way, processing returns again to the step 1502.

When the software image encoder and software image decoder shown in Fig. 4 and Fig. 5 are made to execute a program implementing the method of synthesizing interframe predicted images described in this specification, global motion compensation or warping prediction can be performed with a smaller amount of computation. Compared to the case when this invention is not used, therefore, power consumption is reduced, devices are less costly to manufacture, images with more pixels can be processed in real time, and

simultaneous parallel processing can be performed including processing other than encoding and decoding. Moreover, by using the algorithm shown in this specification, compressed image data which could not be reproduced in real time due to limitation of the computing ability of conventional encoders and decoders, can now be reproduced in real time.

The embodiments of this invention described above further comprise the following embodiments.

(1) In conventional image encoding, error coding is performed using discrete cosine transformation or the like after interframe prediction, however this invention may be used for image encoding or decoding when the interframe predicted image is used as the reconstructed image without modification.

(2) In the above description, it was assumed that the shape of the image was rectangular, however the invention may be applied equally well to images having any arbitrary shape other than rectangular. In this case, the processing of the invention may first be applied to a rectangle enclosing an image of arbitrary shape, and a computation performed to calculate motion vectors only of pixels in the image of arbitrary shape.

(3) In the above specification, a motion vector interpolation/extrapolation algorithm was described

using two step processing wherein the value of p or q was a non-negative integer power of 2. However this two-step processing algorithm also has the effect of reducing the numerator of a division even when p and q are not non-negative integer powers of 2, and it is therefore effective for preventing overflow of registers.

Field of the Invention

Fig. 17 shows specific examples of an encoding/decoding device using the prediction image synthesis method shown in this specification.

(a) shows a case where an image coding/decoding software installed in a personal computer 1701 is used as the image encoding/decoding device. This software is recorded on some type of storage medium (CD-ROM, floppy disk or hard disk, etc.,), and read by the personal computer. Further, by connecting this personal computer to a communication line, the device can be used as an image communication terminal.

(b) shows a case where a coded bit stream comprising moving image information encoded by the method of this invention and recorded on a storage medium 1702 is read and reconstructed by a reproducing device 1703 comprising a device according to this invention, and the reconstructed video signal is displayed on a television monitor 1704. The reproducing device 1703 may also simply read the coded

bit stream, the decoding device being built into a television monitor 1704.

(c) shows a case wherein the decoding device of this invention is built into a television receiver 1705 for digital broadcasting.

(d) shows a case wherein the decoder is built into a set-top box 1709 connected to a cable TV cable 1708 or a satellite/terrestrial wave broadcasting antenna, and the image is reproduced on a television monitor 1710.
Instead of the set-top box, the decoder may also be built into the television monitor as in the case of 1704 of (b).

(e) shows a case where the encoder/decoder of this invention is built into a digital portable terminal 1706. The digital portable terminal may be a transmitting/receiving terminal comprising an encoder/decoder, a transmitting terminal only with an encoder, or a receiving terminal only with a decoder.

(f) shows a case where the encoder is built into a camera 1707 for photographing moving images. The camera 1707 may simply acquire a video signal, and the signal be input to a special encoder 1711. In any of the devices or systems shown in the figure, the method described in this specification permits simplification of the device as compared with the case when prior art technology is used.

WHAT IS CLAIMED:

1. A method of synthesizing an interframe predicted image comprising:

a first step for calculating the values of motion vectors of four representative points at coordinates (i,j), (i+p, j), (i, j+q), (i+p, j+q) (where i, j, p, q are integers, the horizontal and vertical components of the motion vectors of the representative points taking the values of integral multiples of 1/k where k is the hk power of 2, and hk is a non-negative integer),

a second step for calculating the motion vectors of a pixel at coordinates (x+w, y+w) by performing bilinear interpolation/extrapolation on the motion vectors of the four representative points of an image where the pixel sampling interval in both the horizontal and vertical directions is 1 and the horizontal and vertical coordinates of the sampling points are obtained by adding w to integers (where w=wn/wd, wn is a non-negative integer, wd is a hw power of 2, hw is a non-negative integer and wn<wd), where the aforesaid second step comprised of :

a third step for calculating the horizontal and vertical components of motion vectors at the coordinates (i, y+w) as numerical values which are respectively integral multiples of 1/z (where z is the

hz power of 2, and hz is a non-negative integer) by linear interpolation/extrapolation of the motion vectors of the representative points at the coordinates (i, j), (i, j+q), and for calculating the horizontal and vertical components of the motion vectors at the coordinates (i+p, y+w) as values which are respectively integral multiples of 1/z (where z is the hz power of 2, and hz is a non-negative integer) by linear interpolation/extrapolation of the motion vectors of the representative points at coordinates (i+p, j), (i+p, j+q), and

a fourth step for calculating the horizontal and vertical components of the motion vectors of the pixel at the coordinates (x+w, y+w) as values which are respectively integral multiples of 1/m (where m is the hm power of 2, and hm is a non-negative integer), found by linear interpolation/extrapolation of the aforesaid two motion vectors at the coordinates (i, y+w), (i+p, y+w).

2. A method of synthesizing an interframe predicted image comprising:

a first step for calculating the values of motion vectors of four representative points at coordinates (i,j), (i+p, j), (i, j+q), (i+p, j+q) (where i, j, p, q are integers, the horizontal and vertical components of the motion vectors of the representative points taking the values of integral

multiples of 1/k where k is the hk power of 2, and hk is a non-negative integer),

a second step for calculating the motion vectors of a pixel at coordinates (x+w, y+w) by performing bilinear interpolation/extrapolation on the motion vectors of four representative points of an image where the pixel sampling interval in both the horizontal and vertical directions is 1 and the horizontal and vertical coordinates of the sampling points are obtained by adding w to integers (where w=wn/wd, wn is a non-negative integer, wd is a hw power of 2, hw is a non-negative integer and wn<wd), where the aforesaid second step comprised of :

a third step for calculating the horizontal and vertical components of motion vectors at the coordinates (x+w, j) as numerical values which are respectively integral multiples of 1/z (where z is the hz power of 2, and hz is a non-negative integer) by linear interpolation/extrapolation of the motion vectors of the representative points at the coordinates (i, j), (i+p, j), and for calculating the horizontal and vertical components of the motion vectors at the coordinates (x+w, j+q) as values which are respectively integral multiples of 1/z (where z is the hz power of 2, and hz is a non-negative integer) by linear interpolation/extrapolation of the motion vectors of

the representative points at coordinates (i, j+q), (i+p, j+q), and

a fourth step for calculating the horizontal and vertical components of the motion vectors of the pixel at the coordinates (x+w, y+w) as values which are respectively integral multiples of 1/m (where m is the hm power of 2, and hm is a non-negative integer), found by linear interpolation/extrapolation of the aforesaid two motion vectors at the coordinates (x+w, j), (x+w, j+p).

3. A method of synthesizing an interframe prediction image as defined in Claim 1, wherein, when the motion vectors of a pixel at the coordinates (x+w, y+w) are found using (u0, v0), (u1, v1), (u2, v2), (u3, v3), which are the horizontal and vertical components of the motion vectors of the representative points at the coordinates (i,j), (i+p, j), (i, j+q), (i+p, j+q) multiplied by k, (uL(y+w), vL(y+w)) which are the horizontal and vertical components of the motion vectors at a point having the coordinates (i, y+w) multiplied by z, are found by calculating:

uL(y+w)=(((q.wd-y.wd-wn)u0+(y.wd+wn)u2)z)////(q.k.wd),

vL(y+w)=(((q.wd-y.wd-wn)v0+(y.wd+wn)v2)z)////(q.k.wd)

(where [////] is a division wherein the computation result is rounded to the nearest integer when the

result of an ordinary division is not an integer, and the order of computational priority is equivalent to multiplication and division),

uR(y+w), vR(y+w)) which are the horizontal and vertical components of the motion vector at a point having the coordinates (i+p, y+w) multiplied by z, are found by calculating:

uR(y+w)=(((q.wd-y.wd-wn)u1+(y.wd+wn)u3)z)////(q.k.wd)

vR(y+w)=(((p.wd-y.wd-wn)v1+(y.wd+wn)v3)z)////(q.k.wd), and

(u(x+w), y+w), v(x+w, y+w)) which are the horizontal and vertical components of the motion vector of a pixel at the coordinates (x+w, y+w) multiplied by m, are found by calculating:

u(x+w, y+w)=(((p.wd-x.wd-wn)uL(y+w)+(x.wd+wn)uR(y+w))m)//(p.z.wd)

v(x+w, y+w)=(((p.wd-x.wd-wn)vL(y+w)+(x.wd+wn)vR(y+w))m)//(p.z.wd)

(where [//] is a division wherein the computation result is rounded to the nearest integer when the result of an ordinary division is not an integer, and the order of priority is equivalent to multiplication and division).

4. A method of synthesizing an interframe prediction image as defined in Claim 2, wherein, when the motion vectors of a pixel at the coordinates (x+w, y+w) are

found using (u0, v0), (u1, v1), (u2, v2), (u3, v3), which are the horizontal and vertical components of the motion vectors of the representative points at the coordinates (i,j), (i+p, j), (i, j+q), (i+p, j+q) multiplied by k,

(uT(x+w), vT(x+w)) which are the horizontal and vertical components of the motion vectors at a point having the coordinates (x+w, j) multiplied by z, are found by calculating:

uT(x+w)=(((p.wd-x.wd-wn)u0+(x.wd+wn)u1)z)////(p.k.wd),

vT(x+w)=(((p.wd-x.wd-wn)v0+(x.wd+wn)v1)z)////(p.k.wd)

(where [////] is a division wherein the computation result is rounded to the nearest integer when the result of an ordinary division is not an integer, and the order of computational priority is equivalent to multiplication and division),

uB(y+w), vB(y+w)) which are the horizontal and vertical components of the motion vectors at a point having the coordinates (x+w, j+p) multiplied by z, are found by calculating: uB(x+w)=(((p.wd-x.wd-wn)u2+(x.wd+wn)u3)z)////(p.k.wd) vB(x+w)=(((p.wd-x.wd-wn)v2+(x.wd+wn)v3)z)////(p.k.wd), and

(u(x+w), y+w), v(x+w, y+w)) which are the horizontal and vertical components of the motion vectors of a pixel at the coordinates (x+w, y+w) multiplied by m, are found by calculating:

u(x+w, y+w)=(((q.wd-y.wd-
wn)uT(x+w)+(y.wd+wn)uB(x+w))m)//(q.z.wd)

v(x+w, y+w)=(((q.wd-y.wd-
wn)vT(x+w)+(y.wd+wn)vB(x+w))m)//(q.z.wd)

(where [//] is a division wherein the computation result is rounded to the nearest integer when the result of an ordinary division is not an integer, and the order of priority is equivalent to multiplication and by division).

5. A method of synthesizing an interframe predicted image as defined in Claim 1, wherein the absolute value of p is the α power of 2 (where a is a non-negative integer).

6. A method of synthesizing an interframe predicted image as defined in Claim 2 or 4, wherein the absolute value of q is the β power of 2 (where β is a non-negative integer).

7. A method of synthesizing an interframe predicted image as defined in Claim 1, wherein the absolute values of p and q are respectively the α power of 2 and β power of 2 (where α, β are non-negative integers).

8. A method of synthesizing an interframe predicted image as defined in Claim 2, wherein the absolute

values of p and q are respectively the α power of 2 and β power of 2 (where α, β are non-negative integers).

9. A method of synthesizing an interframe predicted image as defined in Claim 5, wherein α+hz is a positive integral multiple of 8, and w is 0.

10. A method of synthesizing an interframe predicted image as defined in Claim 6, wherein β+hz is a positive integral multiple of 8, and w is 0.

11. A method of synthesizing an interframe predicted image as defined in Claim 5, wherein α+hz+hw is a positive integral multiple of 8, and w>0.

12. A method of synthesizing an interframe predicted image as defined in Claim 6, wherein β+hz+hw is a positive integral multiple of 8, and w>0.

13. A method of synthesizing an interframe predicted image as defined in Claim 9, wherein the value of hz is varied according to the value of α so that α+hz is 16 or less for plural different values of α.

14. A method of synthesizing an interframe predicted image as defined in Claim 10, wherein the value of hz

is varied according to the value of β so that β+hz is 16 or less for plural different values of β.

15. A method of synthesizing an interframe predicted image as defined in Claim 11, wherein the value of hz is varied according to the value of α so that α+hz+hw is 16 or less for plural different values of α.

16. A method of synthesizing an interframe predicted image as defined in Claim 12, wherein the value of hz is varied according to the value of β so that β+hz+hw is 16 or less for plural different values of β.

17. A method of synthesizing an interframe predicted image as defined in any of Claims 1 to 16, wherein $z \geq m$.

18. A method of synthesizing an interframe predicted image as defined in any of Claims 1 to 17, wherein $k \geq z$.

19. A method of synthesizing an interframe predicted image as defined in any of Claims 1 to 18, wherein the absolute values of p and q are respectively different from the number of horizontal and vertical pixels in the image.

20. A method of synthesizing an interframe predicted image as defined in any of Claims 1 to 19, wherein, when r is the number of pixels in the horizontal

direction and s is the number of pixels in the vertical direction of the image (where r, s are positive integers), 1/2 of the absolute value of p is less than r, the absolute value of p is equal to or greater than r, 1/2 of the absolute value of q is less than s, and the absolute value of q is equal to or greater than s.

21. A method of synthesizing an interframe predicted image as defined in any of Claims 1 to 19, wherein, when r is the number of pixels in the horizontal direction and s is the number of pixels in the vertical direction of the image (where r, s are positive integers), the absolute value of p is equal to or less than r, twice the absolute value of p is larger than r, the absolute value of q is equal to or less than s, and twice the absolute value of q is larger than s.

22. A method of synthesizing an interframe predicted image as defined in any of Claims 1 to 21, wherein,

when the number of pixels in the horizontal and vertical directions of the image is respectively r and s (where r and s are positive integers), and the pixels of the image lie in a range wherein the horizontal coordinate is from 0 to less than r and the vertical coordinate is from 0 to less than s,

(u0, v0), (u1, v1), (u2, v2), (u3, v3)

which are expressed by

u'(x, y)=(((s.cd-cn-y.cd)((r.cd-cn-x.cd)u00 + (x.cd+cn)u01) + (y.cd+cn)((r.cd-cn-x.cd)u02+(x.cd+cn)u03))k) ///(r.s.n.cd),

v'(x, y)=(((s.cd-cn-y.cd)((r.cd-cn-x.cd)v00 + (x.cd+cn)v01) + (y.cd+cn)((r.cd-cn-x.cd)v02+(x.cd+cn)v03))k) ///(r.s.n.cd),

u0=u'(i, j)

v0=v'(i, j)

u1=u'(i+p, j)

v1=v'(i+p, j)

u2=u'(i, j+q)

v2=v'(i, j+q)

u3=u'(i+p, j+q)

v3=v'(i+p, j+q)

(where [///] is a division wherein the computation result is rounded to the nearest integer when the result of an ordinary division is not an integer, and the order of priority is equivalent to multiplication and division), are used as the k times horizontal and vertical components of motion vectors of representative points (i,j), (i+p, j), (i, j+q), (i+p, j+q), by using (u00, v00), (u01, v01), (u02, v02), (u03, v03) (where u00, v00, u01, v01, u02, v02, u03, v03 are integers), which are n times (where n is a positive integer) motion vectors at the corners of an image situated at the coordinates (-c, -c), (r-c, -c), (-c, s-c), (r-c, s-c) (where c=cn/cd, cn is a non-negative integer, cd is a positive integer and cn<cd), whereof the

horizontal and vertical components take the values of integral multiples of 1/n.

23. An image encoding method using a method of synthesizing an interframe predicted image comprising:

a first step for outputting a difference between an image signal of a current frame which is to be encoded and an interframe predicted image as a differential image,

a second step for transforming the signal of said differential image to obtain a transformed signal which is then encoded,

a fourth step for applying an inverse transformation to said transformed signal to produce a decoded differential image of said differential image, and

a fifth step for producing an interframe predicted image signal for the frame immediately following said current frame image signal using said decoded differential image and said interframe predicted image, wherein

said fifth step is performed by an interframe predicted image synthesis method as defined in any of Claims 1 to 16.

24. An image coding method as defined in Claim 23, wherein said fifth step comprises a step for detecting

and encoding information relating to motion vectors of the representative points.

25. An image coding method as defined in Claim 23, wherein the representative points in said fifth step are the corners of the image.

26. An image decoding method comprising:

a first step for inputting an interframe coding signal of an image frame which is to be decoded and motion vector information concerning said image frame,

a second step for transforming said interframe coding signal into a decoded differential signal,

a third step for producing an interframe predicted image from a decoded image signal of another image frame different in time form said image to be decoded and said motion vector information, and

a fourth step for adding the decoded differential signal and said interframe predicted image signal to obtain a decoded image signal of said image frame which is to be decoded, wherein

said third step is performed by an interframe predicted image synthesis method as defined in any of Claims 1 to 16.

27. An image decoding method as defined in Claim 26, wherein said plural representative points are the corner points of said image used by reproducing

information relating to the motion vectors of the representative points directly encoded as encoded data.

28. An image decoding method as defined in Claim 26, wherein said plural representative points are the corner points of said image.

29. An encoding device comprising an encoder which encodes an image signal of a current frame to be encoded, an interframe predicted image and part of the output of a first transforming unit which transforms the image signal, a second transforming unit which applies an inverse transformation to part of the output of the first transforming unit to obtain a decoded differential image of said differential image, decoding means which obtains a decoded image of the signal of the current frame from said decoded differential image and said interframe predicted image, and a motion compensating unit which adds the decoded image of said immediately preceding frame and the input image of said current frame to synthesize said interframe predicted image, wherein:

said motion compensating unit comprises a global motion vector estimating unit for calculating the values of motion vectors of four representative points at coordinates (i,j), (i+p, j), (i, j+q), (i+p, j+q) (where i, j, p, q are integers, the horizontal and vertical components of the motion vectors of the

representative points taking the values of integral multiples of 1/k where k is the hk power of 2, and hk is a non-negative integer) of said decoded image of the immediately preceding frame from the decoded image of said immediately preceding frame and the input image of the current frame, and a predicted image synthesizing unit for producing an interframe predicted image which predicts the signal of the current frame to be encoded from said motion vectors and the decoded image of said immediately preceding frame, and

said predicted image synthesizing unit comprises a computing unit for calculating the motion vectors of a point at coordinates (i, y+w) by performing bilinear interpolation/extrapolation on the motion vectors of representative points situated at coordinates (i, j),
(i, j+q) of an image lying on a number of sampling points obtained by adding an integer w to the horizontal and vertical coordinates when a pixel sampling interval in both the horizontal and vertical directions is 1 (where w=wn/wd, wn is a non-negative integer, wd is a hw power of 2, hw is a non-negative integer and wn<wd), calculating the horizontal and vertical components of motion vectors at the coordinates (i, y+w) as numerical values which are respectively integral multiples of 1/z (where z is the hz power of 2, and hz is a non-negative integer) by linear interpolation/extrapolation of the motion

vectors of representative points at the coordinates (i, j), (i, j+q), calculating the horizontal and vertical components of the motion vectors at the coordinates (i+p, y+w) as values which are respectively integral multiples of 1/z (where z is the hz power of 2, and hz is a non-negative integer) by linear interpolation/extrapolation of the motion vectors of the representative points at coordinates (i+p, j), (i+p, j+q), and calculating the horizontal and vertical components of the motion vectors of the pixel at the coordinates (x+w, y+w) as values which are respectively integral multiples of 1/m (where m is the hm power of 2, and hm is a non-negative integer) by linear interpolation/extrapolation of the aforesaid two motion vectors at the coordinates (i, y+w), (i+p, y+w), and

a synthesizing unit for synthesizing a predicted image from the motion vectors of a pixel situated at the aforesaid coordinates (x+w, y+w) and the decoded image of said immediately preceding frame.

30. An encoding device comprising a subtractor which outputs a difference between an image signal of a current frame to be encoded and an interframe predicted image signal as a differential image, an encoder which encodes part of the output of a first transforming unit for transforming the signal of said differential image, a second transforming unit which applies an inverse transformation to part of the output of the first

transforming unit to obtain a decoded differential image of said differential image, decoding means which obtains a decoded image of the current frame from said decoded differential image and said interframe predicted image, and a motion compensating unit which uses the decoded image of said immediately preceding frame and an input image 601 of said current frame to synthesize said interframe predicted image, wherein

said motion compensating unit comprises a global motion vector estimating unit for calculating the values of motion vectors of four representative points at coordinates (i,j), (i+p, j), (i, j+q), (i+p, j+q) (where i, j, p, q are integers, the horizontal and vertical components of the motion vectors of the representative points taking the values of integral multiples of 1/k where k is the hk power of 2, and hk is a non-negative integer) of said decoded image of the immediately preceding frame from the decoded image of said immediately preceding frame and the input image of the current frame, and a predicted image synthesizing unit for producing an interframe predicted image which predicts the signal of the current frame to be encoded from said motion vectors and the decoded image of said immediately preceding frame, and

said predicted image synthesizing unit comprises a computing unit for calculating the motion vectors of a point at coordinates (x+w, j) by performing bilinear interpolation/extrapolation on the

motion vectors of representative points situated at coordinates (i, j), (i+p, j) of an image where the pixel sampling interval in both the horizontal and vertical directions is 1 and the horizontal and vertical coordinates of the sampling points are obtained by adding to integhers (where w=wn/wd, wn is a non-negative integer, wd is a hw power of 2, hw is a non-negative integer and wn<wd), calculating the horizontal and vertical components of motion vectors at the coordinates (x+w, j+q) as numerical values which are respectively integral multiples of 1/z (where z is the hz power of 2, and hz is a non-negative integer) by linear interpolation/extrapolation of the motion vectors of the representative points at the coordinates (i, j+q), (i+p, j+q), and calculating the horizontal and vertical components of the motion vectors of the pixel at the coordinates (x+w, y+w) as values which are respectively integral multiples of 1/m (where m is the hm power of 2, and hm is a non-negative integer) by linear interpolation/extrapolation of the aforesaid two motion vectors at the coordinates (x+w, j), (x+w, j+p), and

a synthesizing unit for synthesizing a predicted image from the motion vectors of a pixel situated at the aforesaid coordinates (x+w, y+w) and the decoded image of said immediately preceding frame.

31. An encoding device as defined in Claim 29, wherein, when the motion vectors of a pixel at the coordinates (x+w, y+w) are found using (u0, v0), (u1, v1), (u2, v2), (u3, v3), which are the horizontal and vertical components of the motion vectors of the representative points at the coordinates (i,j), (i+p, j), (i, j+q), (i+p, j+q) multiplied by k,

(uL(y+w), vL(y+w)) which are the horizontal and vertical components of the motion vectors at a point having the coordinates (i, y+w) multiplied by z, are found by calculating:

uL(y+w)=(((q.wd-y.wd-wn)u0+(y.wd+wn)u2)z)////(q.k.wd),

vL(y+w)=(((q.wd-y.wd-wn)v0+(y.wd+wn)v2)z)////(q.k.wd)

(where [////] is a division wherein the computation result is rounded to the nearest integer when the result of an ordinary division is not an integer, and the order of computational priority is equivalent to multiplication and division),

uR(y+w), vR(y+w)) which are the horizontal and vertical components of the motion vector at a point having the coordinates (i+p, y+w) multiplied by z, are found by calculating:

uR(y+w)=(((q.wd-y.wd-wn)u1+(y.wd+wn)u3)z)////(q.k.wd) vR(y+w)=(((p.wd-y.wd-wn)v1+(y.wd+wn)v3)z)////(q.k.wd), and

(u(x+w), y+w), v(x+w, y+w)) which are the horizontal and vertical components of the motion vector

of a pixel at the coordinates (x+w, y+w) multiplied by m, are found by calculating:

u(x+w, y+w)=(((p.wd-x.wd-wn)uL(y+w)+(x.wd+wn)uR(y+w))m)//(p.z.wd)

v(x+w, y+w)=(((p.wd-x.wd-wn)vL(y+w)+(x.wd+wn)vR(y+w))m)//(p.z.wd)

(where [//] is a division wherein the computation result is rounded to the nearest integer when the result of an ordinary division is not an integer, and the order of priority is equivalent to multiplication and division).

32. An interframe predicted image encoding device as defined in Claim 30, wherein, when the motion vectors of a pixel at the coordinates (x+w, y+w) are found using (u0, v0), (u1, v1), (u2, v2), (u3, v3), which are the horizontal and vertical components of the motion vectors of the representative points at the coordinates (i,j), (i+p, j), (i, j+q), (i+p, j+q) multiplied by k, (uT(x+w), vT(x+w)) which are the horizontal and vertical components of the motion vectors at a point having the coordinates (x+w, j) multiplied by z, are found by calculating:

uT(x+w)=(((p.wd-x.wd-wn)u0+(x.wd+wn)u1)z)////(p.k.wd),

vT(x+w)=(((p.wd-x.wd-wn)v0+(x.wd+wn)v1)z)////(p.k.wd)

(where [////] is a division wherein the computation result is rounded to the nearest integer when the result of an ordinary division is not an integer, and the order of computational priority is equivalent to multiplication and division),

uB(y+w), vB(y+w)) which are the horizontal and vertical components of the motion vectors at a point having the coordinates (x+w, j+p) multiplied by z, are found by calculating:

uB(x+w)=(((p.wd-x.wd-wn)u2+(x.wd+wn)u3)z)////(p.k.wd) vB(x+w)=(((p.wd-x.wd-wn)v2+(x.wd+wn)v3)z)////(p.k.wd), and

(u(x+w), y+w), v(x+w, y+w)) which are the horizontal and vertical components of the motion vectors of a pixel at the coordinates (x+w, y+w) multiplied by m, are found by calculating:

u(x+w, y+w)=(((q.wd-y.wd-wn)uT(x+w)+(y.wd+wn)uB(x+w))m)//(q.z.wd)

v(x+w, y+w)=(((q.wd-y.wd-wn)vT(x+w)+(y.wd+wn)vB(x+w))m)//(q.z.wd)

(where [//] is a division wherein the computation result is rounded to the nearest integer when the result of an ordinary division is not an integer, and the order of priority is equivalent to multiplication and division).

33. An interframe predicted image encoding device as defined in Claim 29, wherein the absolute value of p is the α power of 2 (where α is a non-negative integer).

34. An interframe predicted image encoding device as defined in Claim 30, wherein the absolute value of q is the β power of 2 (where β is a non-negative integer).

35. An encoding device as defined in Claim 29, wherein the absolute values of p and q are respectively the α power of 2 and β power of 2 (where α, β are non-negative integers).

36. An encoding device as defined in Claim 30, wherein the absolute values of p and q are respectively the α power of 2 and β power of 2 (where α, β are non-negative integers).

37. An encoding device as defined in Claim 33, wherein α+hz is a positive integral multiple of 8, and w is 0.

38. An encoding device as defined in Claim 34, wherein β+hz is a positive integral multiple of 8, and w is 0.

39. An encoding device as defined in Claim 33, wherein α+hz+hw is a positive integral multiple of 8, and w>0.

40. An encoding device as defined in Claim 34, wherein β+hz+hw is a positive integral multiple of 8, and w>0.

41. An encoding device as defined in Claim 37, wherein the value of hz is varied according to the value of a so that α+ hz is 16 or less for plural different values of α.

42. An encoding device as defined in Claim 38, wherein the value of hz is varied according to the value of β so that β+hz is 16 or less for plural different values of β.

43. An encoding device as defined in Claim 39, wherein the value of hz is varied according to the value of α so that α+hz+hw is 16 or less for plural different values of α.

44. An encoding device as defined in Claim 40, wherein the value of hz is varied according to the value of β so that β+hz+hw is 16 or less for plural different values of β.

45. An encoding device as defined in any of Claims 29 to 40, wherein said motion compensating unit further comprises means for encoding information relating to motion vectors of said representative points.

46. An encoding device as defined in any of Claims 29 to 40, wherein said representative points are points at the corners of an image.

47. An encoding device as defined in any of Claims 29 to 40, wherein said first transforming unit and second transforming unit are respectively a circuit which applies a DCT transformation and quantizes the signal of said differential image, and a circuit which performs inverse quantization and an inverse DCT transformation.

48. An image decoding device comprising a transforming unit for transforming a signal of a differential image of an interframe differential code of an encoded image signal, a frame memory for storing a decoded frame image signal, a predicted image synthesizing unit for inputting motion vectors of said encoded image signal and the decoded frame image signal of said frame memory, and synthesizing a predicted image, an adding unit for adding the output of said predicted image synthesizing unit and the output of said transforming circuit to produce a decoded image, and means for storing the output of said adding unit in said frame memory, wherein said predicted image synthesizing unit comprises means for synthesizing an interframe predicted image as defined in any of Claims 1 to 16.

49. A storage medium on which software has been recorded for implementing the method of synthesizing an interframe predicted image as defined in any of Claims 1 to 22.

50. A storage medium on which software has been recorded for driving an image decoding device as defined in Claim 48.

51. A storage medium on which an encoded bit stream generated by an encoding method as defined in Claim 23, 24 or 25 has been recorded.

52. A storage medium on which a compressed, encoded bit stream which can be decoded by an image decoding method as defined in Claim 26, 27 or 28, has been recorded.

ABSTRACT

A method is provided to simplify the computation involved in global motion compensation and warping prediction in coding and decoding of motion compensated image signals. In the synthesis of a global motion compensated predicted image 1203 which predicts a current frame image from an immediately preceding frame image 1202 using motion vectors 1205 of plural representative points having a particular spatial interval in an image frame, a first interpolation/extrapolation 1207 is performed to calculate motion vectors of provisional representative points from motion vectors 1206 of representative points, and a second interpolation/extrapolation 1209 is then performed to calculate motion vectors 1210 for each pixel from motion vectors 1208 of the provisional representative points.

A division performed when the predicted image is synthesized can be replaced by a shift computation involving a smaller number of bits, so the processing carried out by a computer or special hardware can be simplified.

FIG. 1

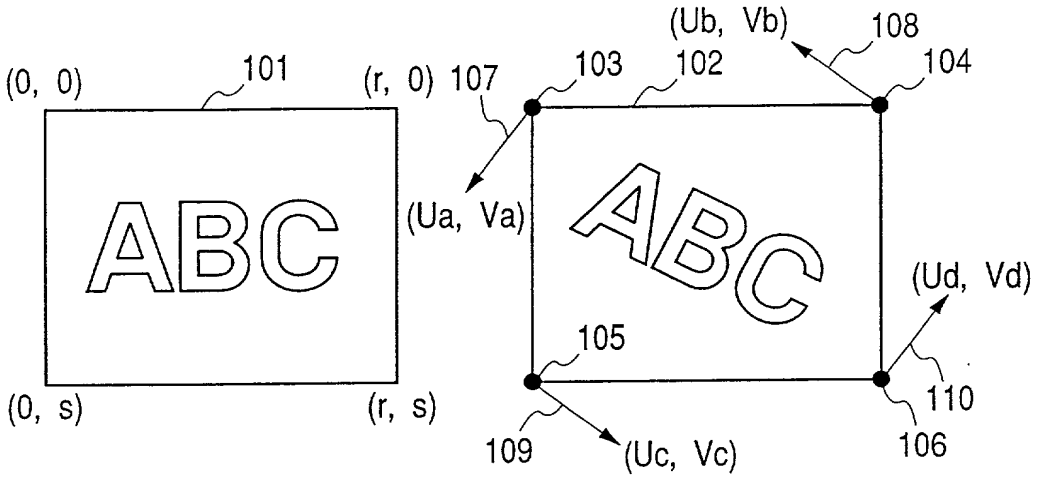

(0, 0)
101
(r, 0)
107
103
102
(Ub, Vb)
108
104
ABC
(Ua, Va)
ABC
(Ud, Vd)
105
110
(0, s)
(r, s)
109
(Uc, Vc)
106

FIG. 3

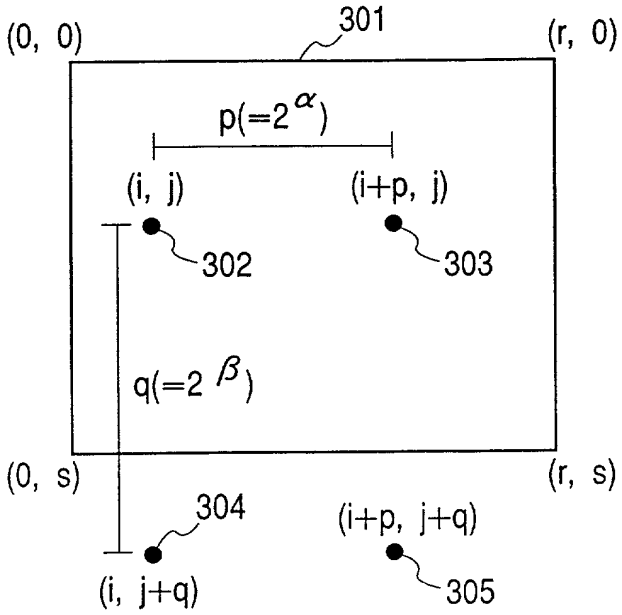

(0, 0)
301
(r, 0)
p(=2^α)
(i, j)
(i+p, j)
302
303
q(=2^β)
(0, s)
(r, s)
304
(i+p, j+q)
(i, j+q)
305

FIG. 2

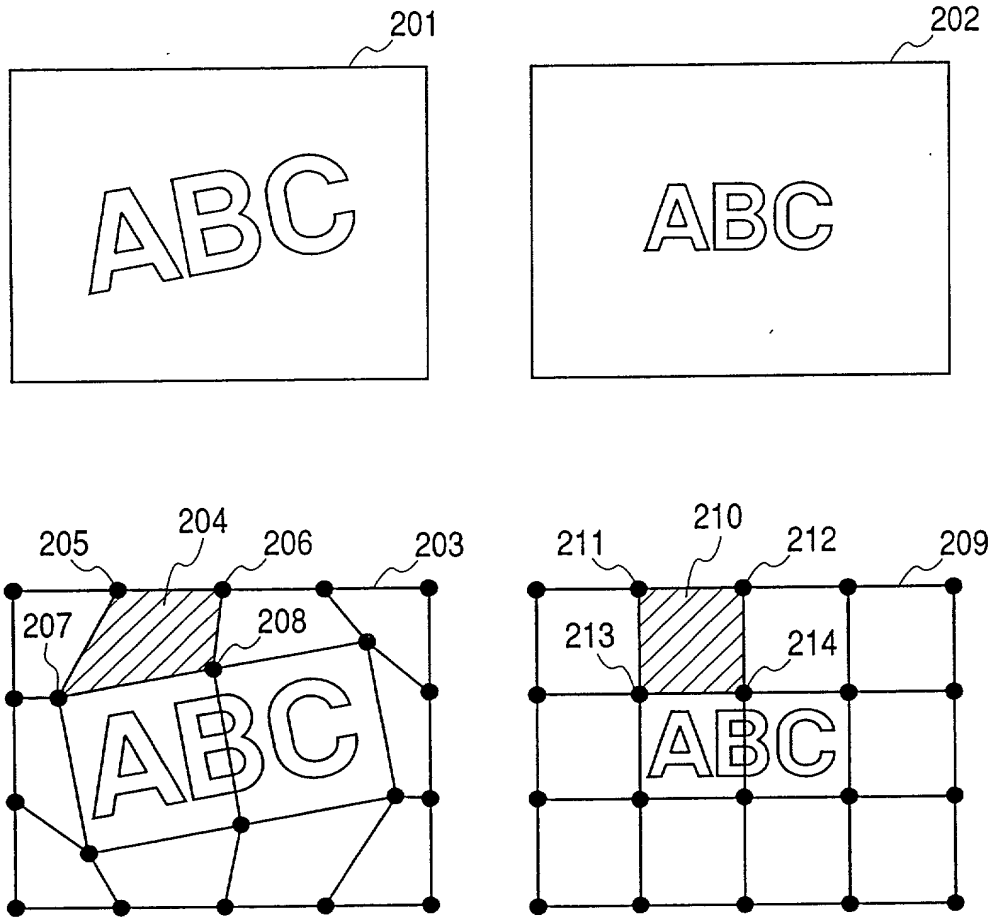

201
202
ABC
ABC
205
204
206
203
207
208
ABC
211
210
212
209
213
214
ABC

FIG. 4

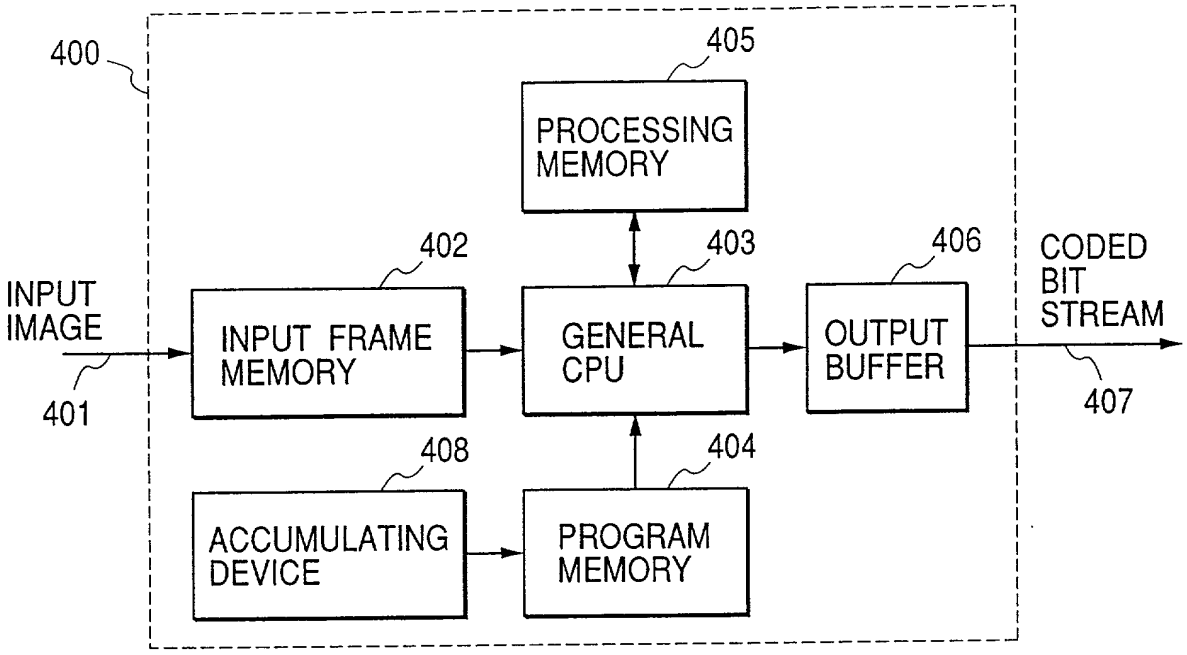

400
405
PROCESSING MEMORY
402
403
406
INPUT IMAGE
INPUT FRAME MEMORY
GENERAL CPU
OUTPUT BUFFER
CODED BIT STREAM
401
407
408
404
ACCUMULATING DEVICE
PROGRAM MEMORY

FIG. 5

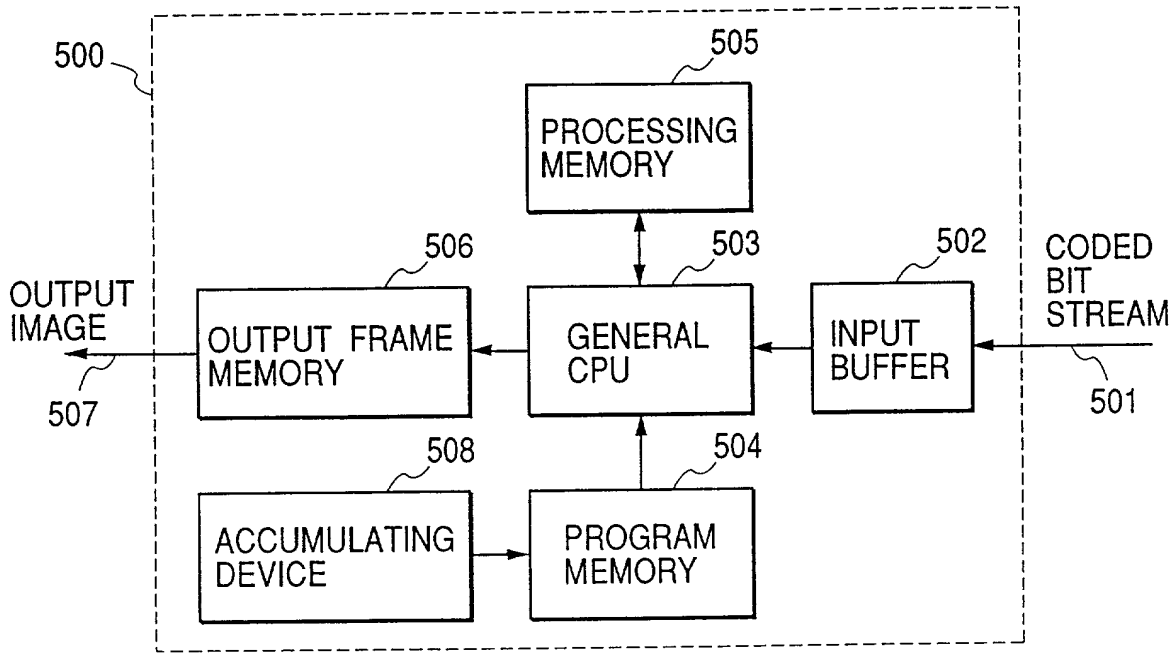

500
505
PROCESSING MEMORY
506
503
502
OUTPUT IMAGE
OUTPUT FRAME MEMORY
GENERAL CPU
INPUT BUFFER
CODED BIT STREAM
507
501
508
504
ACCUMULATING DEVICE
PROGRAM MEMORY

FIG. 6

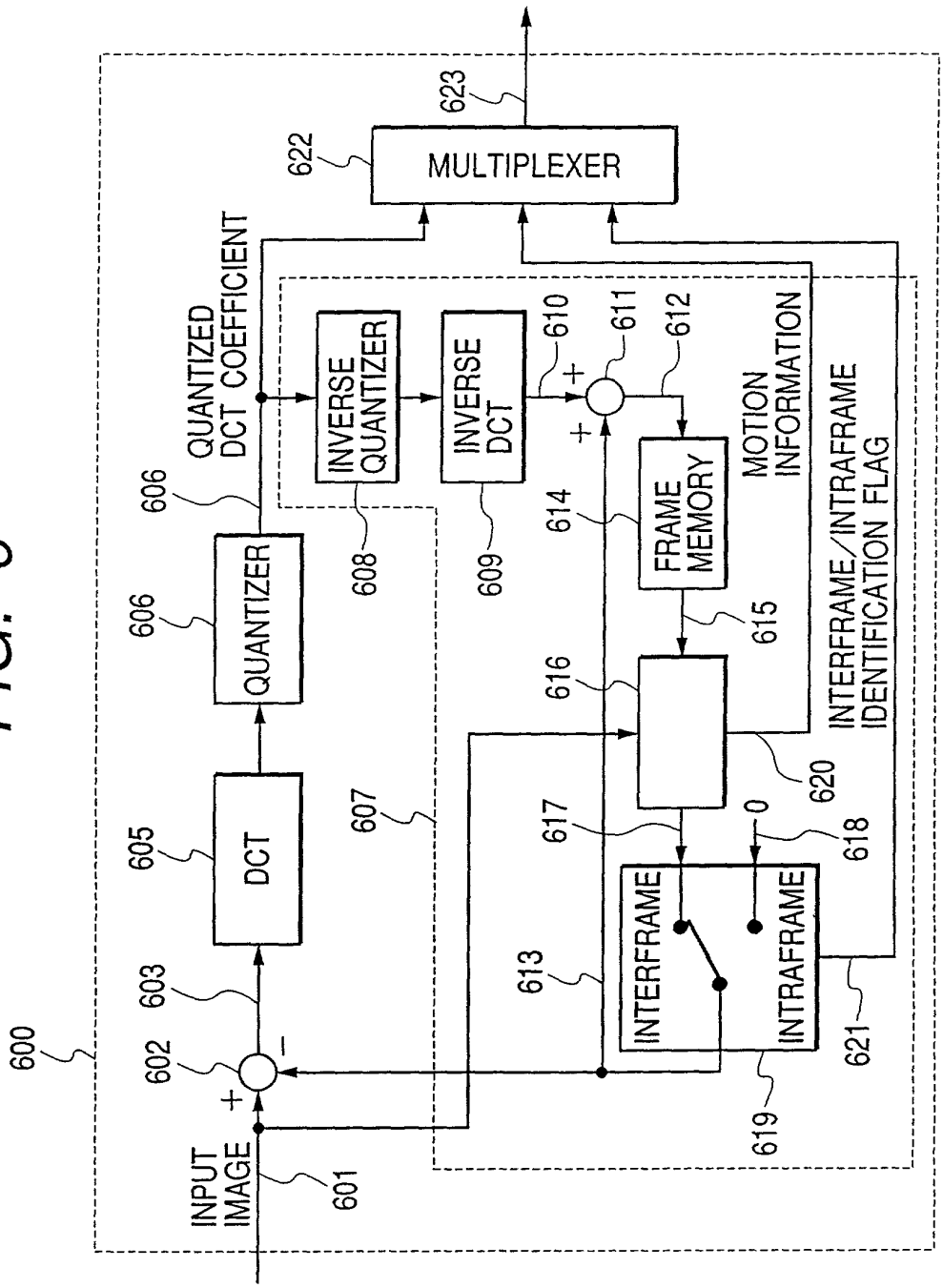

600
INPUT IMAGE
601
602
603
DCT
605
QUANTIZER
606
QUANTIZED DCT COEFFICIENT
606
607
INVERSE QUANTIZER
608
INVERSE DCT
609
610
611
612
FRAME MEMORY
614
615
MOTION INFORMATION
INTERFRAME/INTRAFRAME IDENTIFICATION FLAG
616
620
617
0
618
INTERFRAME
INTRAFRAME
613
619
621
MULTIPLEXER
622
623

FIG. 7

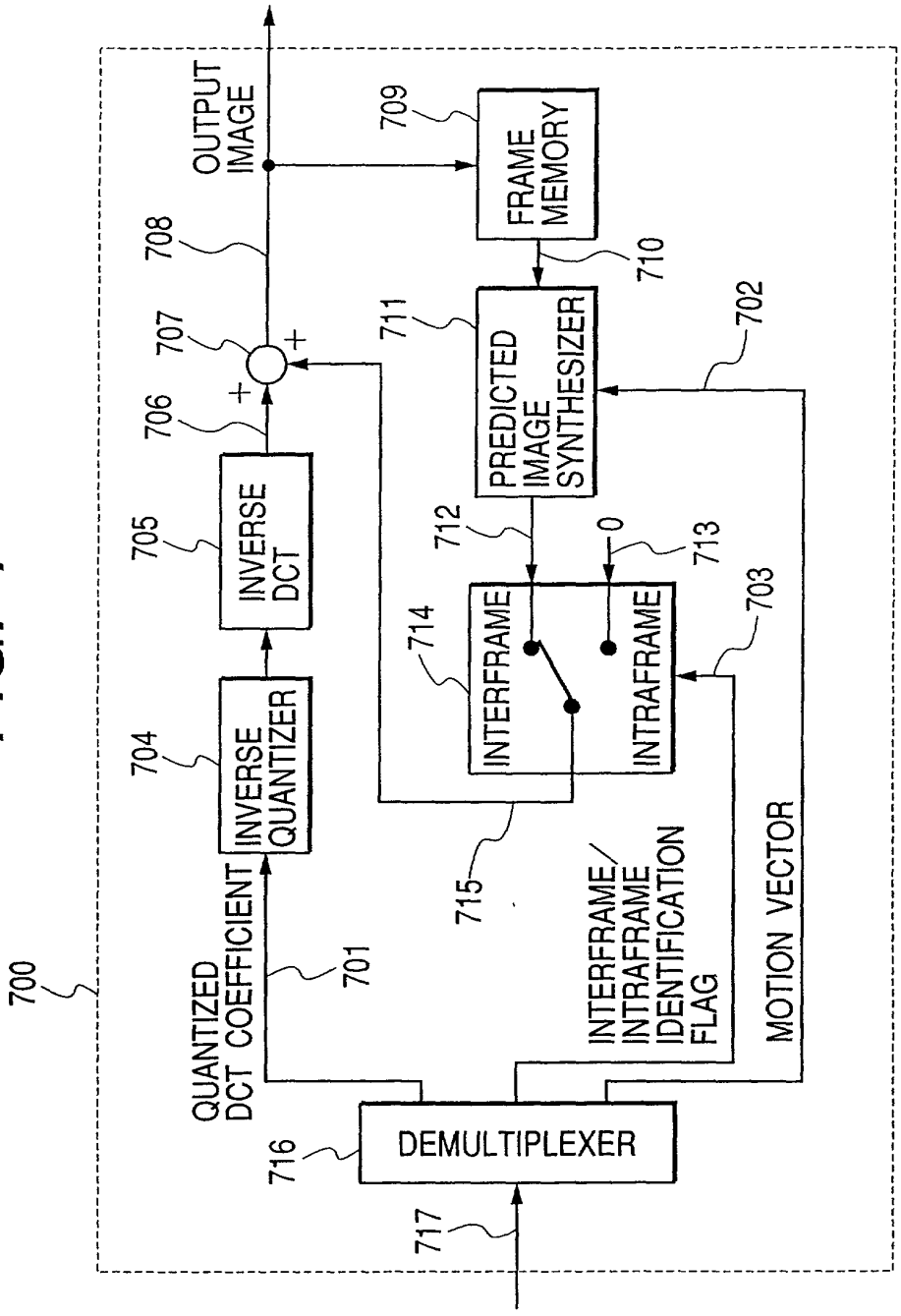

700
QUANTIZED DCT COEFFICIENT
701
INVERSE QUANTIZER
704
INVERSE DCT
705
706
+
707
+
708
OUTPUT IMAGE
709
FRAME MEMORY
710
711
PREDICTED IMAGE SYNTHESIZER
702
712
INTERFRAME
714
0
713
INTRAFRAME
703
715
INTERFRAME/ INTRAFRAME IDENTIFICATION FLAG
MOTION VECTOR
716
DEMULTIPLEXER
717

FIG. 8

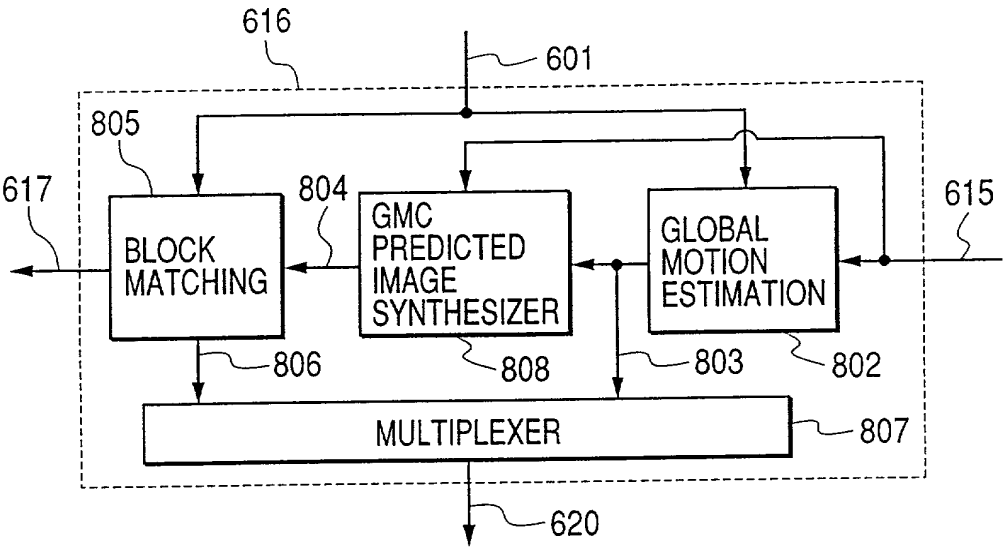

616
601
805
617
804
615
BLOCK MATCHING
GMC PREDICTED IMAGE SYNTHESIZER
GLOBAL MOTION ESTIMATION
806
808
803
802
MULTIPLEXER
807
620

FIG. 9

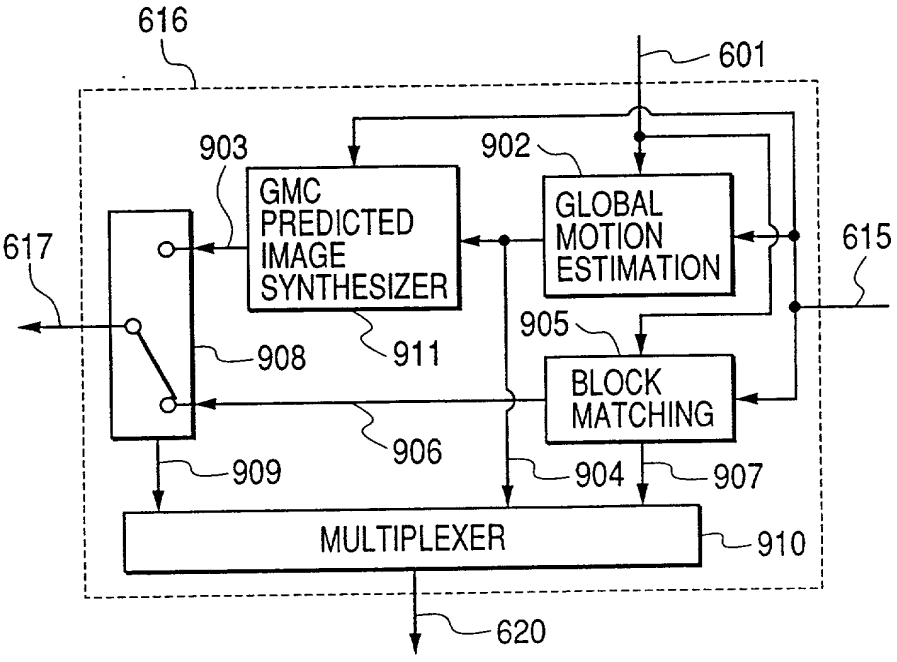

616
601
903
902
617
GMC PREDICTED IMAGE SYNTHESIZER
GLOBAL MOTION ESTIMATION
615
908
911
905
BLOCK MATCHING
906
909
904
907
MULTIPLEXER
910
620

FIG. 10

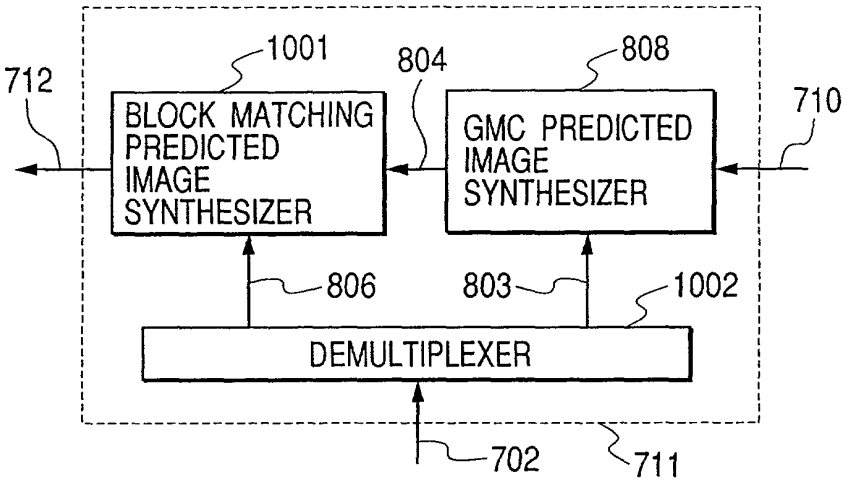

1001
804
808
712
710
BLOCK MATCHING PREDICTED IMAGE SYNTHESIZER
GMC PREDICTED IMAGE SYNTHESIZER
806
803
1002
DEMULTIPLEXER
702
711

FIG. 11

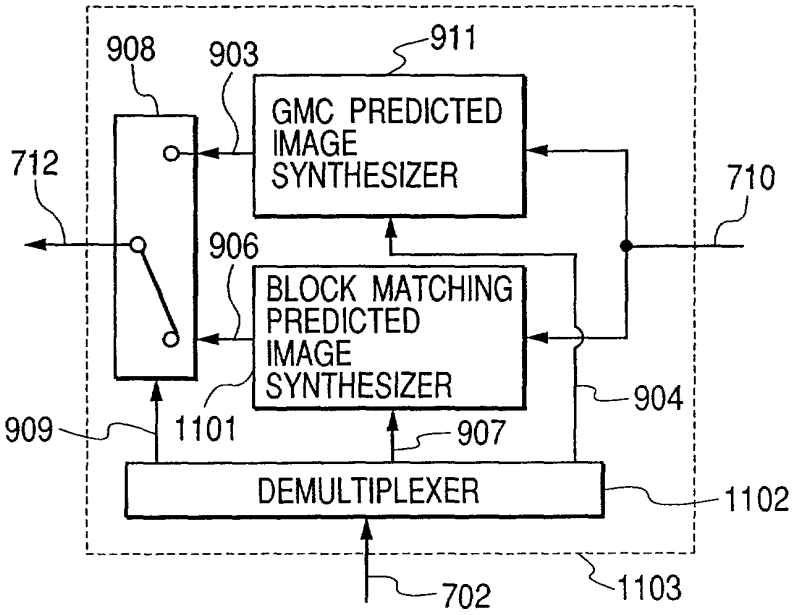

908
903
911
GMC PREDICTED IMAGE SYNTHESIZER
712
710
906
BLOCK MATCHING PREDICTED IMAGE SYNTHESIZER
904
909
1101
907
DEMULTIPLEXER
1102
702
1103

FIG. 12

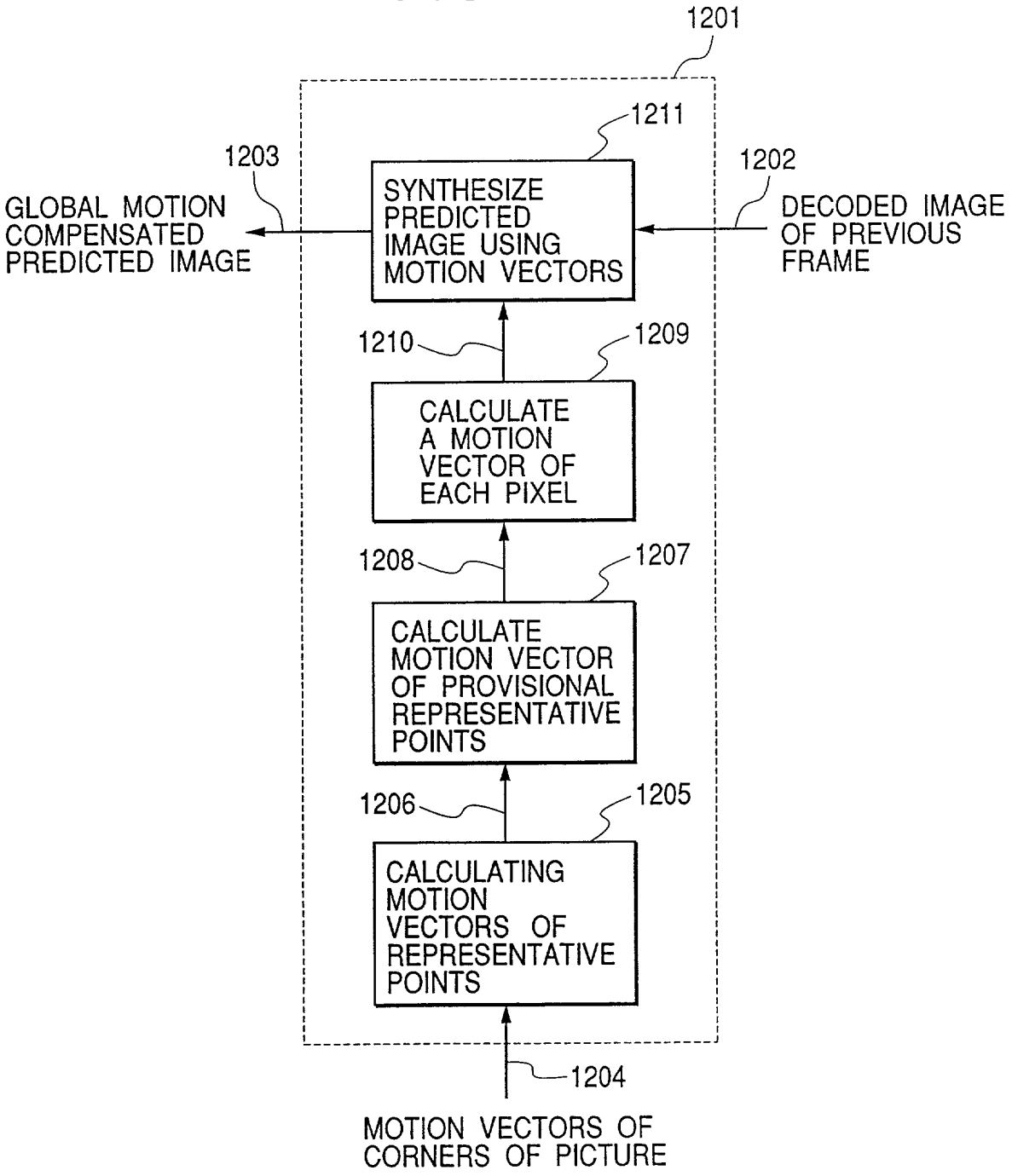

1201
1211
1203
1202
GLOBAL MOTION COMPENSATED PREDICTED IMAGE
SYNTHESIZE PREDICTED IMAGE USING MOTION VECTORS
DECODED IMAGE OF PREVIOUS FRAME
1210
1209
CALCULATE A MOTION VECTOR OF EACH PIXEL
1208
1207
CALCULATE MOTION VECTOR OF PROVISIONAL REPRESENTATIVE POINTS
1206
1205
CALCULATING MOTION VECTORS OF REPRESENTATIVE POINTS
1204
MOTION VECTORS OF CORNERS OF PICTURE

FIG. 13

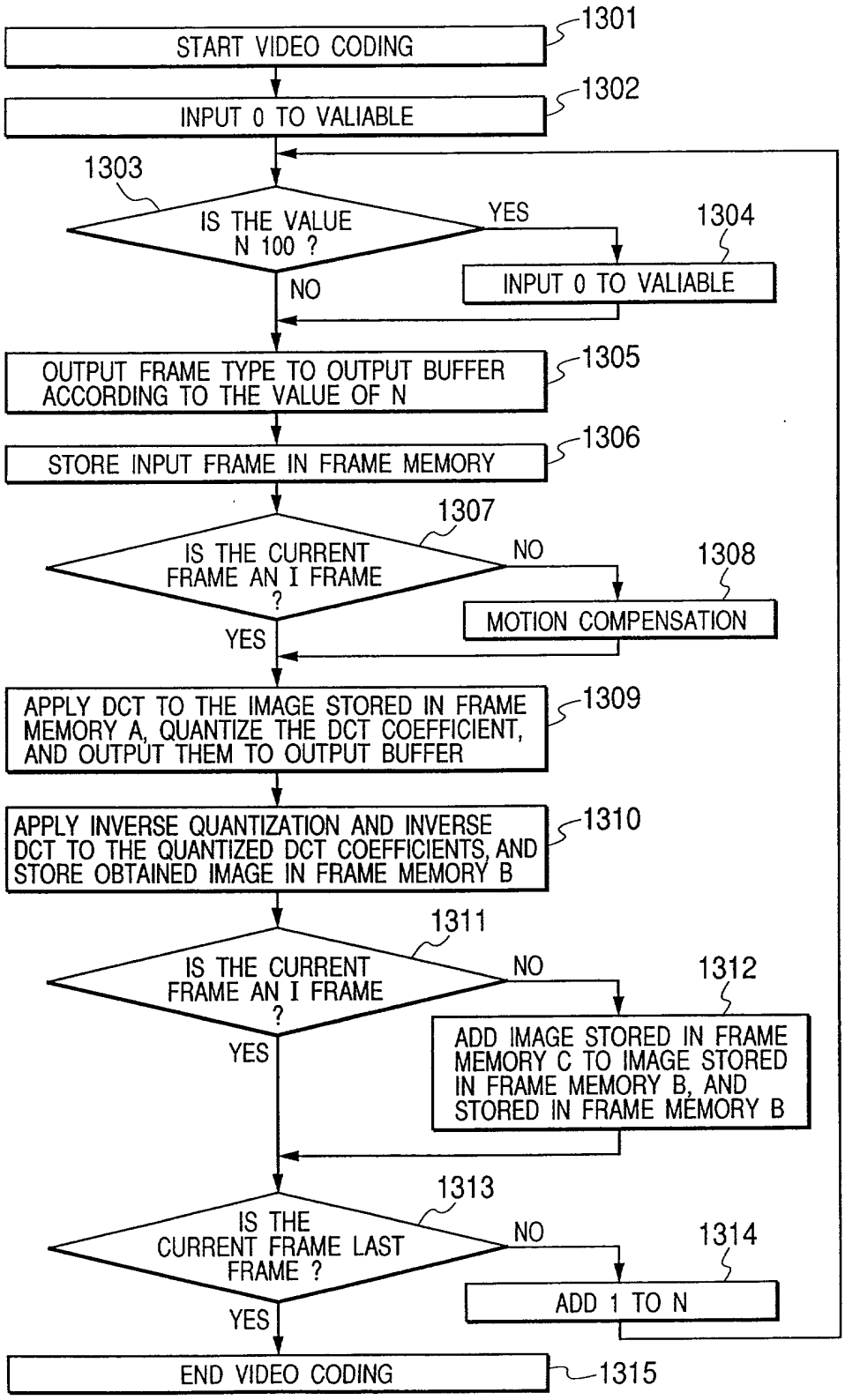

START VIDEO CODING
1301
INPUT 0 TO VALIABLE
1302
1303
IS THE VALUE N 100 ?
YES
1304
INPUT 0 TO VALIABLE
NO
OUTPUT FRAME TYPE TO OUTPUT BUFFER ACCORDING TO THE VALUE OF N
1305
STORE INPUT FRAME IN FRAME MEMORY
1306
1307
IS THE CURRENT FRAME AN I FRAME ?
NO
1308
MOTION COMPENSATION
YES
APPLY DCT TO THE IMAGE STORED IN FRAME MEMORY A, QUANTIZE THE DCT COEFFICIENT, AND OUTPUT THEM TO OUTPUT BUFFER
1309
APPLY INVERSE QUANTIZATION AND INVERSE DCT TO THE QUANTIZED DCT COEFFICIENTS, AND STORE OBTAINED IMAGE IN FRAME MEMORY B
1310
1311
IS THE CURRENT FRAME AN I FRAME ?
NO
1312
ADD IMAGE STORED IN FRAME MEMORY C TO IMAGE STORED IN FRAME MEMORY B, AND STORED IN FRAME MEMORY B
YES
1313
IS THE CURRENT FRAME LAST FRAME ?
NO
1314
ADD 1 TO N
YES
END VIDEO CODING
1315

FIG. 14

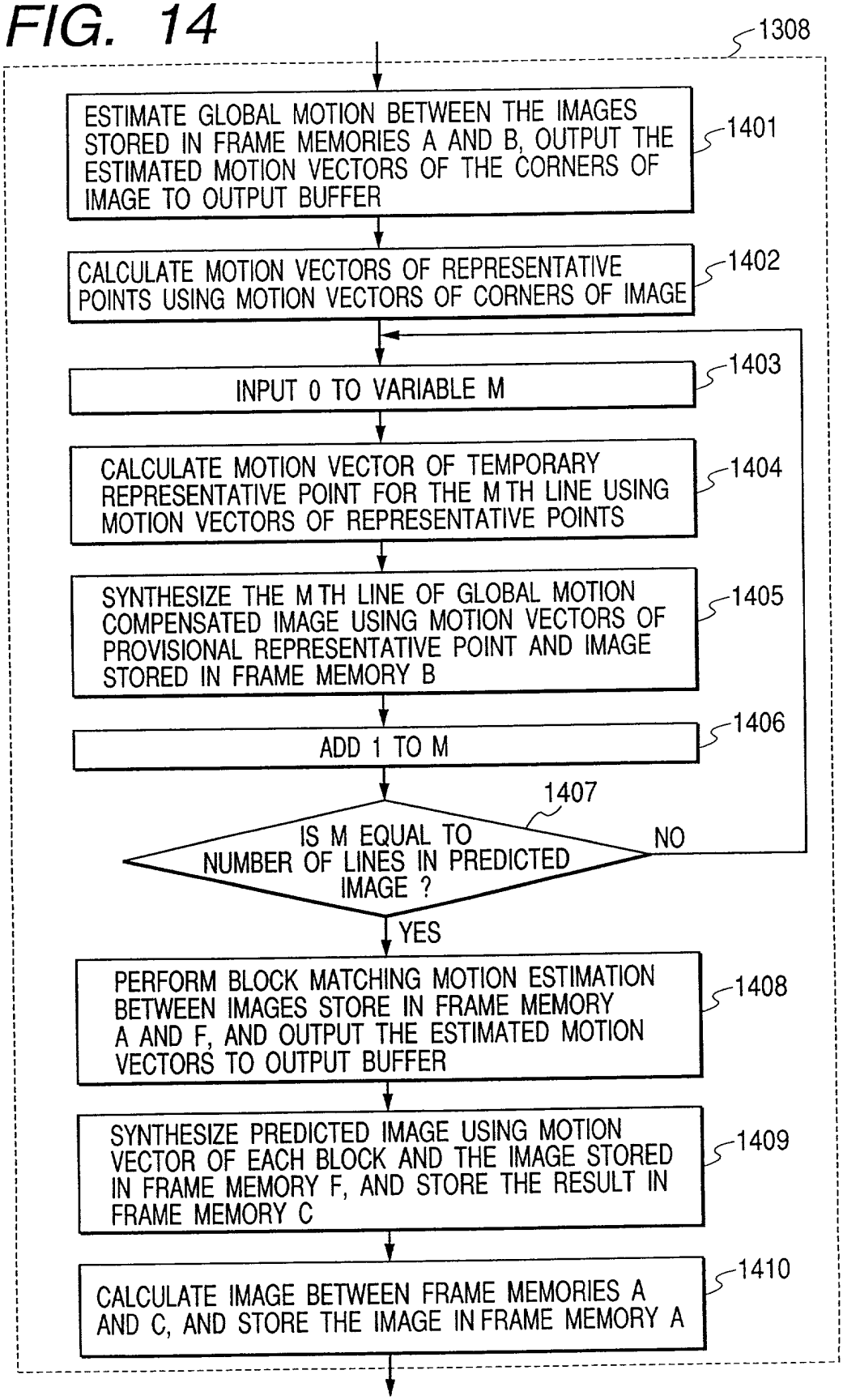

1308
ESTIMATE GLOBAL MOTION BETWEEN THE IMAGES STORED IN FRAME MEMORIES A AND B, OUTPUT THE ESTIMATED MOTION VECTORS OF THE CORNERS OF IMAGE TO OUTPUT BUFFER
1401
CALCULATE MOTION VECTORS OF REPRESENTATIVE POINTS USING MOTION VECTORS OF CORNERS OF IMAGE
1402
INPUT 0 TO VARIABLE M
1403
CALCULATE MOTION VECTOR OF TEMPORARY REPRESENTATIVE POINT FOR THE M TH LINE USING MOTION VECTORS OF REPRESENTATIVE POINTS
1404
SYNTHESIZE THE M TH LINE OF GLOBAL MOTION COMPENSATED IMAGE USING MOTION VECTORS OF PROVISIONAL REPRESENTATIVE POINT AND IMAGE STORED IN FRAME MEMORY B
1405
ADD 1 TO M
1406
1407
IS M EQUAL TO NUMBER OF LINES IN PREDICTED IMAGE ?
NO
YES
PERFORM BLOCK MATCHING MOTION ESTIMATION BETWEEN IMAGES STORE IN FRAME MEMORY A AND F, AND OUTPUT THE ESTIMATED MOTION VECTORS TO OUTPUT BUFFER
1408
SYNTHESIZE PREDICTED IMAGE USING MOTION VECTOR OF EACH BLOCK AND THE IMAGE STORED IN FRAME MEMORY F, AND STORE THE RESULT IN FRAME MEMORY C
1409
CALCULATE IMAGE BETWEEN FRAME MEMORIES A AND C, AND STORE THE IMAGE IN FRAME MEMORY A
1410

FIG. 15

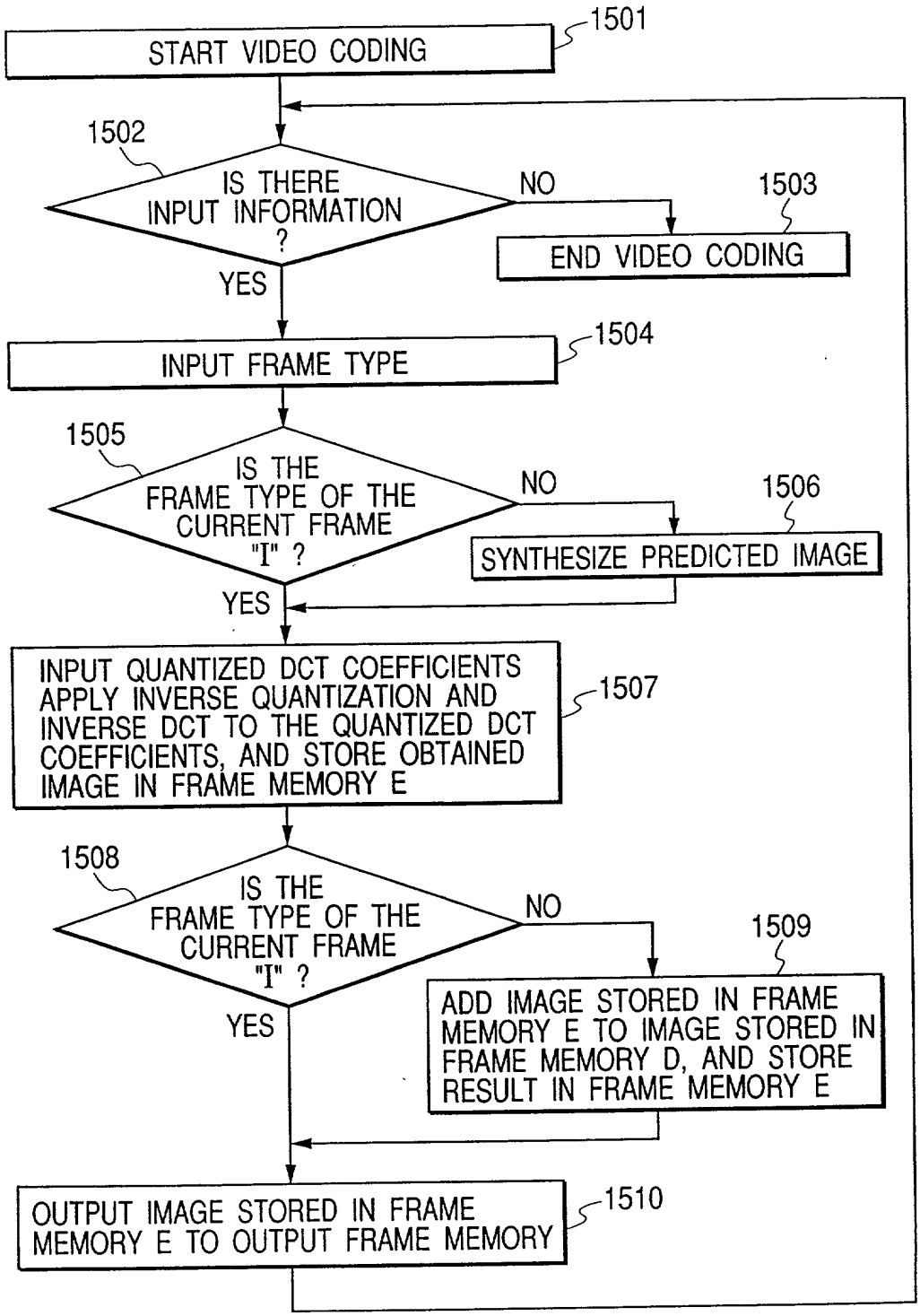

START VIDEO CODING
1501
1502
IS THERE INPUT INFORMATION ?
NO
1503
END VIDEO CODING
YES
INPUT FRAME TYPE
1504
1505
IS THE FRAME TYPE OF THE CURRENT FRAME "I" ?
NO
1506
SYNTHESIZE PREDICTED IMAGE
YES
INPUT QUANTIZED DCT COEFFICIENTS APPLY INVERSE QUANTIZATION AND INVERSE DCT TO THE QUANTIZED DCT COEFFICIENTS, AND STORE OBTAINED IMAGE IN FRAME MEMORY E
1507
1508
IS THE FRAME TYPE OF THE CURRENT FRAME "I" ?
NO
1509
ADD IMAGE STORED IN FRAME MEMORY E TO IMAGE STORED IN FRAME MEMORY D, AND STORE RESULT IN FRAME MEMORY E
YES
OUTPUT IMAGE STORED IN FRAME MEMORY E TO OUTPUT FRAME MEMORY
1510

FIG. 16

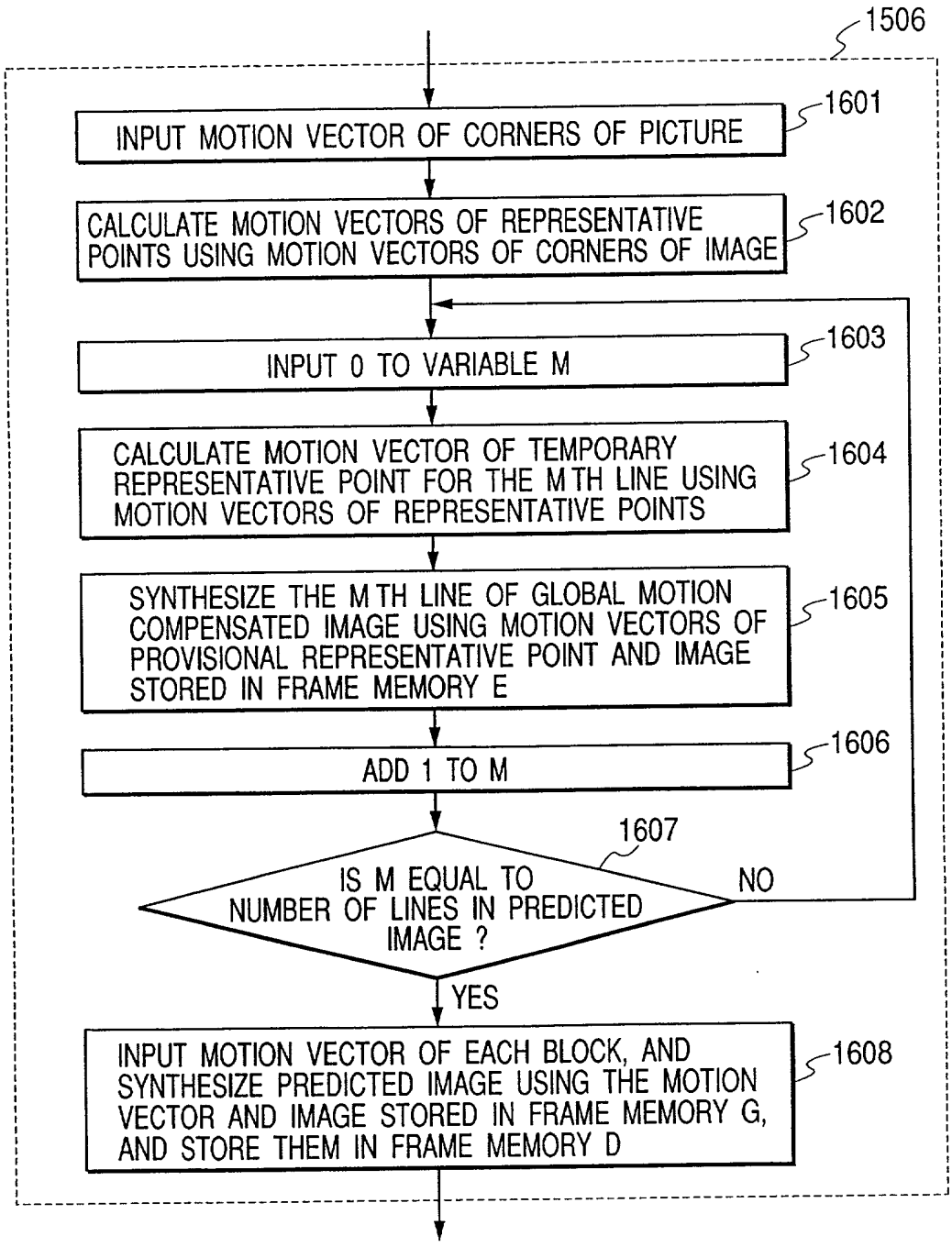
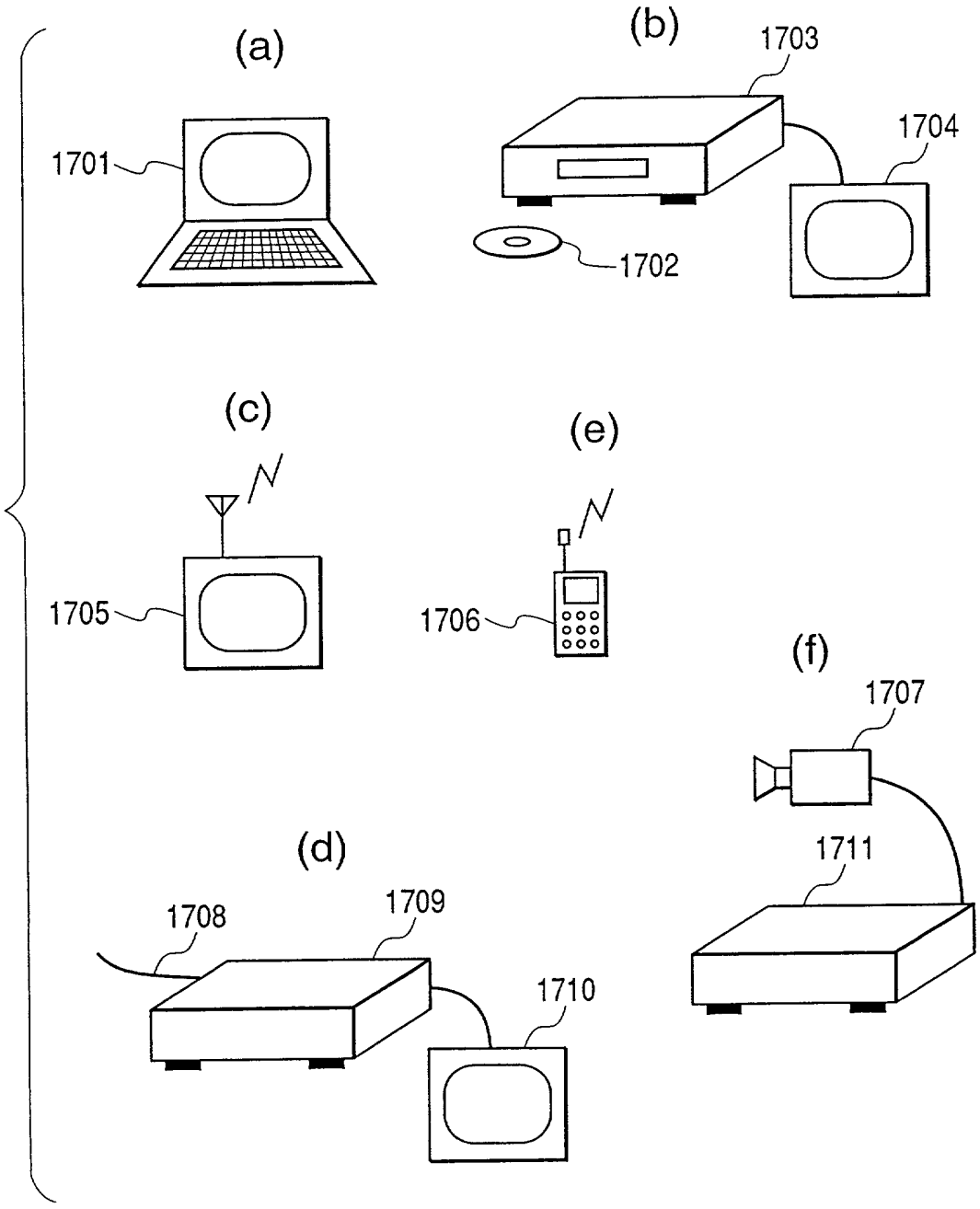

1506
INPUT MOTION VECTOR OF CORNERS OF PICTURE
1601
CALCULATE MOTION VECTORS OF REPRESENTATIVE POINTS USING MOTION VECTORS OF CORNERS OF IMAGE
1602
INPUT 0 TO VARIABLE M
1603
CALCULATE MOTION VECTOR OF TEMPORARY REPRESENTATIVE POINT FOR THE M TH LINE USING MOTION VECTORS OF REPRESENTATIVE POINTS
1604
SYNTHESIZE THE M TH LINE OF GLOBAL MOTION COMPENSATED IMAGE USING MOTION VECTORS OF PROVISIONAL REPRESENTATIVE POINT AND IMAGE STORED IN FRAME MEMORY E
1605
ADD 1 TO M
1606
1607
IS M EQUAL TO NUMBER OF LINES IN PREDICTED IMAGE ?
NO
YES
INPUT MOTION VECTOR OF EACH BLOCK, AND SYNTHESIZE PREDICTED IMAGE USING THE MOTION VECTOR AND IMAGE STORED IN FRAME MEMORY G, AND STORE THEM IN FRAME MEMORY D
1608

FIG. 17


(a)
1701
(b)
1703
1704
1702
(c)
1705
(e)
1706
(f)
1707
1711
(d)
1708
1709
1710

PTO/SB/106(8-96)
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Declaration and Power of Attorney For Patent Application

特許出願宣言書及び委任状

Japanese Language Declaration

日本語宣言書

下記の氏名の発明者として、私は以下の通り宣言します。

As a below named inventor, I hereby declare that.

私の住所、私書箱、国籍は下記の私の氏名の後に記載された通りです。

My residence, post office address and citizenship are as stated next to my name

下記の名称の発明に関して請求範囲に記載され、特許出願している発明内容について、私が最初かつ唯一の発明者（下記の氏名が一つの場合）もしくは最初かつ共同発明者であると（下記の名称が複数の場合）信じています。

I believe I am the original, first and sole inventor (if only one name is listed below) or an original, first and joint inventor (if plural names are listed below) of the subject matter which is claimed and for which a patent is sought on the invention entitled

IMAGE ENCODING AND DECODING METHOD AND DEVICE

上記発明の明細書（下記の欄で×印がついていない場合は、本書に添付）は、

The specification of which is attached hereto unless the following box is checked.

☐ __月__日に提出され、米国出願番号または特許協定条約国際出願番号を_____とし、
(該当する場合) _____に訂正されました。

☒ was filed on June 2,1998
as United States Application Number or
PCT International Application Number
PCT/JP98/02435 and was amended on
_____ (if applicable).

私は、特許請求範囲を含む上記訂正後の明細書を検討し、内容を理解していることをここに表明します。

I hereby state that I have reviewed and understand the contents of the above identified specification, including the claims, as amended by any amendment referred to above

私は、連邦規則法典第３７編第１条５６項に定義されるとおり、特許資格の有無について重要な情報を開示する義務があることを認めます。

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委任状： 私は下記の発明者として、本出願に関する一切の手続きを米特許商標局に対して遂行する弁理士または代理人として、下記の者を指名いたします。（弁護士、または代理人の氏名及び登録番号を明記のこと）

POWER OF ATTORNEY. As a named inventor, I hereby appoint the following attorney(s) and/or agent(s) to prosecute this application and transact all business in the Patent and Trademark Office connected therewith (list name and registration number)

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I hereby claim foreign priority under Title 35, United States Code, Section 119 (a)-(d) or 365(b) of any foreign application(s) for patent or inventor s certificate, or 365(a) of any PCT international application which designated at least one country other than the United States, listed below and have also identified below, by checking the box, any foreign application for patent or inventor s certificate, or PCT International application having a filing date before that of the application on which priority is claimed

Prior Foreign Application(s)
外国での先行出願

(Number) (番号)	(Country) (国名)	(Day/Month/Year Filed) (出願年月日)	Priority Not Claimed 優先権主張なし
9-144916	Japan	3/June/1997	☐
			☐

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(Application No.) (出願番号)	(Filing Date) (出願日)	(Application No) (出願番号)	(Filing Date) (出願日)

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(Application No.) (出願番号)	(Filing Date) (出願日)	(Status Patented, Pending, Abandoned) (現況：特許許可済、係属中、放棄済)
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I hereby declare that all statements made herein of my own knowledge are true and that all statements made on information and belief are believed to be true, and further that these statements were made with the knowledge that willful false statements and the like so made are punishable by fine or imprisonment, or both, under Section 1001 of Title 18 of the United States Code and that such willful false statements may jeopardize the validity of the application or any patent issued thereon